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# **pylablib Documentation**

***Release 1.4.3***

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**CONTENTS:**

<b>1</b>	<b>Related projects</b>	<b>3</b>
<b>2</b>	<b>Citation</b>	<b>5</b>
2.1	Installation . . . . .	5
2.2	Devices overview . . . . .	8
2.3	Data processing . . . . .	109
2.4	Data storage . . . . .	113
2.5	Various utilities . . . . .	117
2.6	Change log . . . . .	120
2.7	pylablib . . . . .	129
<b>3</b>	<b>Indices and tables</b>	<b>1035</b>
	<b>Python Module Index</b>	<b>1037</b>
	<b>Index</b>	<b>1041</b>



PyLabLib aims to provide support for device control and experiment automation. It interfaces with lots of different *devices*, including several different *camera interfaces*, *translational stages*, *oscilloscopes*, *AWGs*, *sensors*, and more. The interface is implemented in a natural way through Python objects, and is easy to understand. For example, here is a complete script which steps *Thorlabs KDC101* stage by 10000 steps ten times, and each time grabs a frame with *Andor iXon camera*:

```
from pylablib.devices import Thorlabs, Andor # import the device libraries
import numpy as np # import numpy for saving

# connect to the devices
with Thorlabs.KinesisMotor("270000000") as stage, Andor.AndorSDK2Camera() as cam:
    # change some camera parameters
    cam.set_exposure(50E-3)
    cam.set_roi(0, 128, 0, 128, hbin=2, vbin=2)
    # start the stepping loop
    images = []
    for _ in range(10):
        stage.move_by(10000) # initiate a move
        stage.wait_move() # wait until it's done
        img = cam.snap() # grab a single frame
        images.append(img)

np.array(images).astype("<u2").tofile("frames.bin") # save frames as raw binary
```

The list of the devices is constantly expanding.

Additional utilities are added to simplify data acquisition, storage, and processing:

- Simplified data processing utilities: convenient *fitting*, *filtering*, *feature detection*, *FFT* (mostly wrappers around NumPy and SciPy).
- Universal multi-level *dictionaries* which are convenient for *storing* heterogeneous data and settings in human-readable format.
- Assorted functions for dealing with *file system* (creating, moving and removing folders, zipping/unzipping, path normalization), *network* (simplified interface for client and server sockets), *strings* (conversion of various Python objects to and from string), and more.
- Tools for GUI generation and advanced multi-threading built on top of Qt5 (*still in development stage: the documentation is incomplete, and the interfaces can change in later versions*)

The library only works on Python 3, and has been most extensively tested on Windows 10 with 64-bit Python. Linux is, in principle, supported, but devices which require manufacturer-provided DLLs (mostly cameras) might, potentially, have problems.

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**Note:** This is documentation for the newer **1.x** version of the library. The older **0.x** documentation can be found at <https://pylablib-v0.readthedocs.io/en/latest/>.

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## RELATED PROJECTS

[Pylablib cam-control](#) - software for universal camera control and camera data acquisition.





## CITATION

If you found this package useful in your scientific work, you can cite via [Zenodo](#) either referencing to the package in general using the DOI [10.5281/zenodo.7324875](#), or to a specific version, as found on the [Zenodo](#) page.

## 2.1 Installation

### 2.1.1 Standard install

You can install the library from PyPi:

```
pip install pylablib
```

If you already have it installed, you can upgrade it to get the newest version:

```
pip install -U pylablib
```

This will install the full set of dependencies: basic dependencies and computing packages (`numpy`, `scipy`, `pandas`, `numba`, `rpyc`), basic device communication packages (`pyft232`, `pyvisa`, `pyserial`, `pyusb`), and PyQt5-based GUI (`pyqt5` and `pyqtgraph`). You can also install additional device library dependencies (`nidaqmx` and `websocket-client`) using the extra requirements feature of pip:

```
pip install -U pylablib[devio-full]
```

### 2.1.2 Minimal install

In case you do not want some of these packages installed, or they are unavailable on your platform, you can install a lightweight version of `pylablib` called `pylablib-lightweight`. It contains exactly the same code, but has only the most basic dependencies (`numpy`, `scipy`, and `pandas`):

```
pip install -U pylablib-lightweight
```

With this, the basic functionality (such as data processing or file IO) will work, but more advanced features such as device communication and GUI, will require additional packages. In most cases, the raised errors will notify which packages are missing. These can be installed either manually, or using the extra requirements:

- [extra] extra packages used in some situations: `numba` (speeds up some data processing) and `rpyc` (communication between different PCs)
- [devio] basic devio packages: `pyft232`, `pyvisa`, `pyserial`, and `pyusb`
- [devio-extra] additional devio packages: `nidaqmx` and `websocket-client`

- [gui-pyqt5] [PyQt5](#)-based GUI: `pyqt5` and `pyqtgraph`. Should not be used together with [gui-pyside2]
- [gui-pyside2] [PySide2](#)-based GUI: `pyside2` and `pyqtgraph`. Should not be used together with [gui-pyqt5]

The options can be combined. For example,

```
pip install pylablib-lightweight[extra,devio,gui-pyside2]
```

installs the dependencies as the usual pylablib distribution, but with PySide2 Qt5 backend instead of PyQt5.

### 2.1.3 Anaconda install

The package is also available on Anaconda via `conda-forge` channel. To install it, run

```
conda install -c conda-forge pylablib
```

in the Anaconda prompt.

The Anaconda version of pylablib comes with all the standard dependencies except for `pyft232`, `nidaqmx` and `websocket-client`, which are not available on `conda-forge` channel. This means, that [Thorlabs APT/Kinesis](#), [NI DAQs](#), and some functionality of [M2 Solstis laser](#) are not accessible. To use those, it is recommended to either install those packages explicitly via `pip` (keep in mind that it can break Anaconda environment), or use a standalone Python distribution.

### 2.1.4 Usage

To access to the most common features simply import the library:

```
import pylablib as pll
# Create a parameter dictionary (e.g., for some processing script)
parameters = pll.Dictionary({"par/x":1, "par/y":2, "par/z":[3,4,5], "out":"result"})
pll.save_dict(parameters, "parameters.dat") # save parameters to a text file
```

More advanced features (e.g., *device communication*) should be imported directly:

```
from pylablib.devices import Andor # import Andor devices module
cam = Andor.AndorSDK2Camera() # connect to Andor SDK2 camera (e.g., iXon)
cam.set_exposure(0.1) # set exposure to 100ms
frame = cam.snap() # grab a single frame
cam.close() # close the connection
```

### 2.1.5 Dependencies and requirements

The basic package dependencies are [NumPy](#) for basic computations and overall array interface, [SciPy](#) for advanced computations (interpolation, optimization, special functions), and [pandas](#) for heterogeneous tables (`DataFrame`). In addition, it is recommended to have [Numba](#) package to speed up some computations. Finally, if you use options for remote computing and communication between different PCs, you need to install [RPyC](#). Note that when installed directly from `pip`, `numpy` comes with the OpenBLAS version of the linear algebra library; if other version (e.g., Intel MKL) is preferred, it is a good idea to have `numpy` already installed before installing pylablib.

The main device communication packages are [PyVISA](#) and [pySerial](#), which cover the majority of devices. Several devices (e.g., [Thorlabs Kinesis](#) and [Attocube ANC 350](#)) require additional communication packages: [pyft232](#) and

PyUSB. Finally, some particular devices completely or partially rely on specific packages: NI-DAQmx for *NIDAQ* and *websocket-client* for additional *M2 Solstis* functionality.

Finally, GUI and advanced multi-threading relies on Qt5, which has two possible options. The first (default) option is PyQt5 with sip for some memory management functionality. Note that while newer PyQt5 versions  $\geq 5.11$  already come with PyQt5-sip, older versions require a separate sip installation. Hence, if you use an older PyQt5 version, you need to install sip separately. The second possible Qt5 option is PySide2 with shiboken2. Both PyQt5 and PySide2 should work equally well, and the choice mostly depends on what is already installed, because having both PyQt5 and PySide2 might lead to conflicts. Finally, plotting relies on pyqtgraph, which, starting with version 0.11m is compatible with both PySide2 and PyQt5.

The package has been tested with Python 3.6 through 3.9, and is incompatible with Python 2. The last version officially supporting Python 2.7 is 0.4.0. Furthermore, testing has been mostly performed on 64-bit Python. This is the recommended option, as 32-bit version limitations (most notably, limited amount of accessible RAM) mean that it should only be used when absolutely necessary, e.g., when some required packages or libraries are only available in 32-bit version.

## 2.1.6 Installing from GitHub

The most recent and extensive, but less tested and documented, version of this library is available on GitHub at <https://github.com/AlexShkarin/pyLabLib/>. There are several versions of installing it:

- Install using pip using GitHub as a library source:

```
pip install -U git+https://github.com/AlexShkarin/pyLabLib.git
```

- Download it as a zip-file and unpack it into any appropriate place (can be folder of the project you're working on, Python site-packages folder, or any folder added to PATH or PYTHONPATH variable).

To download the code of a specific version, you can choose it in the dropdown *Branch* menu under *Tags* tab. This is the same code as available on PyPi.

Keep in mind that, unlike the first method, the required packages will not be automatically installed, so this has to be done manually:

```
pip install numpy scipy pandas numba rpyc
pip install pyft232 pyvisa pyserial pyusb nidaqmx websocket-client
pip install pyqt5 pyqtgraph
```

- Clone the repository to your computer In order to easily get updates in order to easily get updates. For that, you need to install Git (<https://git-scm.com/>), and use the following commands in the command line (in the folder where you want to store the library):

```
git clone https://github.com/AlexShkarin/pyLabLib
cd ./pyLabLib
```

Whenever you want to update to the most recent version, simply type

```
git pull
```

in the library folder. Keep in mind that any changes that you make to the library code might conflict with the new version that you pull from GitHub, so you should not modify anything in this folder if possible.

## 2.1.7 Support and feedback

If you have any issues, suggestions, or feedback, you can either raise an issue on GitHub at <https://github.com/AlexShkarin/pyLabLib/issues>, or send an e-mail to [pylablib@gmail.com](mailto:pylablib@gmail.com).

## 2.2 Devices overview

Basic concepts are described at the *general device communication page*.

Currently supported devices:

- *Cameras*
  - *Andor SDK2* and *Andor SDK3*: variety of Andor (currently part of Oxford Instruments) cameras. Tested with Andor iXon, Luca, Newton, Zyla, Neo and Marana.
  - *Allied Vision Bonito* cameras: CameraLink-interfaced cameras. Tested with Bonito CL-400B/C and NI IMAQ frame grabber.
  - *Basler*: Basler pylon-compatible cameras. Tested with an emulated Basler camera.
  - *BitFlow*: BitFlow Axion family frame grabbers. Tested with BitFlow Axion 1xB frame grabber together with PhotonFocus MV-D1024E camera.
  - *DCAM*: Hamamatsu cameras. Tested with Hamamatsu Orca Flash 4.0 and ImagEM.
  - *NI IMAQ*: National Instruments frame grabbers. Tested with NI PCI-1430 and PCI-1433 frame grabbers together with PhotonFocus MV-D1024E camera.
  - *NI IMAQdx*: National Instruments universal camera interface. Tested with Ethernet-connected PhotonFocus HD1-D1312 camera.
  - *Photon Focus*: Photon Focus pfcam interface. Tested with PhotonFocus MV-D1024E camera connected through either NI frame grabbers (PCI-1430 and PCI-1433) or Silicon Software frame grabbers (microEnable IV AD4-CL).
  - *PCO SC2*: PCO cameras. Tested with pco.edge cameras with CLHS and regular CameraLink interfaces, and with pco.pixelfly usb cameras.
  - *Picam*: Princeton Instruments cameras. Tested with a PIXIS 400 camera.
  - *PVCAM*: Photometrics cameras. Tested with a Prime 95B camera.
  - *Silicon Software*: Silicon Software frame grabbers. Tested with microEnable IV AD4-CL frame grabbers together with PhotonFocus MV-D1024E camera.
  - *Thorlabs Scientific Cameras*: Thorlabs sCMOS cameras. Tested with Thorlabs Kiralux camera.
  - *Uc480/uEye*: multiple cameras, including simple Thorlabs and IDS cameras. Tested with IDS SC2592R12M and Thorlabs DCC1545M.
  - *Mightex*: several different USB camera types with different APIs. Implemented and tested only for S-series cameras.
- *Stages*
  - *Attocube ANC300* and *Attocube ANC350*: most common Attocube positioner controllers. Tested with Ethernet and USB connection for ANC300, and USB connection for ANC350.
  - *Thorlabs APT/Kinesis*: basic Thorlabs motorized stages and optomechanics devices. Tested with KDC101, K10CR1, and BSC201 motor controllers, KIM101 piezo motor controller, KPZ101 piezo controllers, as well as MFF101 and FW102 (described at a *different page*)

- *Thorlabs Elliptec*: resonant piezoelectric Thorlabs stages. Tested with ELL18 and ELL14 rotational mounts.
- *Newport Picomotor*: precision piezo-actuated screws based on slip-stick principle. Tested with Newport 8742 Picomotor driver using Ethernet or USB connection.
- *Arcus Performax*: fairly common single- and multi-axis motor controllers sold under different brands: Arcus, Nippon Pulse America, or Newmark Systems. Tested with PMX-4EX device with USB connection.
- *Trinamic*: universal motor controllers and drivers. Tested with a single-axis TMCM-1110 controller with USB connection.
- *Standa*: Standa motorized positioners. Tested with a 8SMC4-USB single-axis controller and 8MT167-25 stepper motor stage.
- *SmarAct*: high-performance piezo sliders. Currently simple open-loop *SCU controllers* and *MCS2 controllers* are supported. Tested with a standard HCU controller unit and an MCS2 controller with several SLx stages.
- *Physik Instrumente*: piezo controllers. So far only PI E-515 and PI E-516 is supported and tested.
- *Basic sensors*
  - *HighFinesse*: laser wavelength meters. Tested with WS6 and WS7 USB-controlled devices.
  - *Ophir*: optical power and energy meters. Tested with Ophir Vega.
  - *Thorlabs*: optical power and energy meters. Tested with PM160.
  - *Lakeshore*: temperature sensors. Tested with Lakeshore 218.
  - *Cryocon*: temperature sensors. Tested with CryoCon 14C.
  - *Cryomagnetics*: liquid nitrogen or helium level sensor. Tested with LM-500 and LM-510 sensors.
  - *Pfeiffer*: pressure gauges. Tested with TPG261 and DPG202 controllers.
  - *Leybold*: pressure gauges. Tested with ITR90 gauge.
  - *Kurt J. Lesker*: pressure gauges. Tested with KJL300 gauge.
  - *Agilent*: pressure gauges. Tested with XGS-600 controller and FRG700 gauge.
  - *Thorlabs quadrature detector controller*. Tested with TPA101.
  - *Keithley multimeters*. Tested with model 2110.
  - *Voltcraft multimeters*. Tested with VC-7055BT and VC880.
- *Lasers*
  - *Basic lasers*
    - \* *Lighthouse Photonics SproutG*
    - \* *Laser Quantum Finesse*
  - *M2 Solstis laser and external mixing module*
  - *Toptica iBeam Smart laser*
  - *Hubner Cobolot*
  - *Sirah Matisse laser*
  - *NKT Photonics lasers*
- *Tektronix oscilloscopes*. Tested with TDS2002B, TDS2004B, and DPO2004B.

- *NI DAQs*. Tested with NI USB-6008, NI USB-6343, and NI PCIe-6323.
- *Generic AWGs*. Tested with Agilent 33500 and 33220A, Rigol DG1022, Tektronix AFG1022, GW Instek AFG2225 and AFG2115, and RS Comp AFG21005.
- *Andor spectrographs*. Tested with Kymera 328i spectrograph connected via an Andor Newton camera through I2C interface.
- *Miscellaneous Thorlabs devices*: *MFF101/102* motorized flip mirror mount, *FW102/212* motorized filter wheel, and *MDT693/694* high-voltage source.
- *Miscellaneous OZOptics devices*: *EPC04* fiber polarization controller, *DD100* motorized fiber attenuator, and *TF100* motorized fiber filter.
- *Lumel devices*: *RE72* temperature controller
- *Miscellaneous devices*
  - *Conrad relay board*
  - *Basic Arduino communication*
  - *ElektroAutomatik power supplies*
  - *Rigol power supplies*
- *Generic Windows devices*
- *Mid-level protocols*
  - *Modbus*

## 2.2.1 Basics of device communication

The devices are represented as Python objects. In most cases, one object controls one device, although sometimes one object can be responsible for multiple interconnected devices (e.g., when daisy-chaining of several devices is used, as in *Picomotor stage*). All the device control functions are contained within the class. Occasionally, there are auxiliary function present for listing available devices, dealing with data generated by the device, or adjusting global parameters.

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**Note:** Some specific devices functionality might not be completely covered in the current release. If this is the case for your device, you can let the developers know by raising an [issue on GitHub](#), or sending an e-mail to [pylablib@gmail.com](mailto:pylablib@gmail.com).

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### Connection

The device identifier or address needs to be provided upon the device object creation, after which it is automatically connected. Getting the address usually depends on the kind of device:

- Simple message-style devices, such as AWG, oscilloscopes, sensors and gauges, require an address which depends on the exact connection protocol. For example, serial devices addresses look like "COM1" (or "/dev/ttyUSB0" or Linux), Visa addresses as "USB0::0x1313::0x8070::000000::INSTR", and network addresses take IP and, possibly, port "192.168.1.3:7230". To get the list of all connected devices, you can run `comm_backend.list_backend_resources()`:

```
>> import pylablib as pll
>> pll.list_backend_resources("serial") # list serial port resources
['COM38', 'COM1', 'COM36', 'COM3']
```

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```
>> pll.list_backend_resources("visa") # note that, by default, visa also includes
↳ all the COM ports
('USB0::0x1313::0x8070::000000::INSTR',
'ASRL1::INSTR',
'ASRL3::INSTR',
'ASRL10::INSTR',
'ASRL36::INSTR',
'ASRL38::INSTR')
```

Network devices do not easily provide such functionality (and there are, in principle, many unrelated devices connected to the network), so you might need to learn the device IP elsewhere. Usually, it is set on the device front panel or using some kind of configuration tool and a different connection, such as serial or USB.

In most cases, the connection address is all you need. However, sometimes the connection might require some additional information. The most common situations are ports for the network connection and baud rates for the serial connections. Ports can be supplied either as a part of the string "192.168.1.3:7230", or as a tuple ("192.168.1.3", 7230). The baud rates are, similarly, provided as a tuple: ("COM1", 19200). By default, the devices would use the baud rate which is most common for them, but in some cases (e.g., if the device baud rate can be changed), you might need to provide it explicitly. If it is provided incorrectly, then no communication can be done, and requests will typically return a timeout error:

```
>> from pylablib.devices import Ophir
>> meter = Ophir.VegaPowerMeter("COM3") # for this power meter 9600 baud are used
↳ by default
>> meter.get_power() # let us assume that the devices is currently set up with
↳ 38400 baud
...
OphirBackendError: backend exception: 'timeout during read'
>> meter.close() # need to close the connection before reopening
>> meter = Ophir.VegaPowerMeter(("COM3",38400)) # explicitly specifying the
↳ correct baud rate
>> meter.get_power()
1E-6
```

- More complicated devices using custom DLLs (usually cameras or some translation stages) will have more unique methods of addressing individual devices: serial number, device index, device ID, etc. In most cases such devices come with `list_devices` or `get_devices_number` functions, which give the necessary information.

After communication is done, the connection needs to be closed, since in most cases it can only be opened in one program or part of the script at a time. It also implies that usually it's impossible to connect to the device while its manufacturer software is still running.

The devices have open and close methods, but they can also work in together with Python with statements:

```
# import Thorlabs device classes
from pylablib.devices import Thorlabs

# connect to FW102 motorized filter wheel
wheel = Thorlabs.FW("COM1")
# set the position
wheel.set_position(1)
# close the connection (until that it's impossible to establish a different connection to
↳ this device)
wheel.close()
```

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```
# a better approach
with Thorlabs.FW("COM1") as wheel: # connection is closed automatically when leaving the_
    ↪with-block
    wheel.set_position(1)
```

Because the devices are automatically connected on creation, `open` method is almost never called explicitly. It is generally only used to reconnect to the device after the connection has been previously closed, although in this case creating a new device object would work just as well.

## Operation

The devices are controlled by calling their methods; attributes and properties are very rarely used. Effort is made to maintain consistent naming conventions, e.g., most getter-methods will start with `get_` and setter methods with `set_` or `setup_` (depending on the complexity of the method). It is also common for setter methods to return the new value as a result, which is useful in CLI operation and debugging. Devices of the same kind have the same names for similar or identical functions: most stages have `move_by`, `jog` and `stop` methods, and cameras have `wait_for_frame` and `read_multiple_images` methods. Whenever it makes sense, these methods will also have the same signatures.

## Asynchronous operation and multi-threading

For simplicity of usage and construction, devices interfaces are designed to be synchronous and single-threaded. Asynchronous operation can be achieved by explicit usage of Python multi-threading. Furthermore, the device classes are not designed to be thread safe, i.e., it is not recommended to use the same device simultaneously from two separate threads. However, non-simultaneous calling of device methods from different threads (synchronized, e.g., using locks) or simultaneous usage of several separate devices of the same class is supported.

## Error handling

Errors raised by the devices are usually specific to the device and manufacturer, e.g., `AttocubeError` or `TrinamicError`. These can be obtained from the module containing the device class, or from the class itself as `Error` attribute:

```
>> from pylablib.devices import Attocube
>> atc = Attocube.ANC300("192.168.1.1")
>> atc.disable_axis(1)
>> atc.move_by(1,10) # move on a disabled axis raises an error for ANC300
...
AttocubeError: Axis in wrong mode
>> try:
..     atc.move_by(1,10)
.. except atc.Error: # could also write "except Attocube.AttocubeError"
..     print("Can not move")
Can not move
```

All of the device errors inherit from `DeviceError`, which in turn is a subclass of `RuntimeError`. Therefore, one can also use those exception classes instead:

```
>> import pylablib as pll
>> try:
```

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```

..     atc.move_by(1,10)
.. except pll.DeviceError:
..     print("Can not move")
Can not move

```

## Getting more information

A lot of information about the devices can be gained just from their method names and descriptions (docstrings). There are several ways of getting these:

- In many cases your IDE (PyCharm, Spyder, VS Code with installed Python extension) supports code inspection. In this case, the list of methods will usually pop up after you type the device object name and a dot (such as `cam.`), and the method docstring will show up after you type the method name and parenthesis (such as `cam.get_roi()`). However, sometimes it might take a while for these pop-ups to show up.
- You can use console, such as Jupyter QtConsole, Jupyter Notebook, or a similar console built into the IDE. Here the list of methods can be obtained using the autocomplete feature: type name of the class or object with a dot (such as `cam.`) and then press Tab. The list of all methods should appear. To get the description of a particular class or method, type it with a question mark (such as `cam?` or `cam.get_roi?`) and execute the result (Enter or Shift-Enter, depending on the console). A description should appear with the argument names and the description.
- You can also use the auto-generated documentation within this manual through the search bar: simply type the name of the class or the method (such as `AndorSDK3Camera` or `AndorSDK3Camera.get_roi`) and look through the results. However, the formatting of the auto-generated documentation might be a bit overwhelming.

## Universal settings access

All devices have `get_settings` and `apply_settings` methods which, correspondingly, return Python dictionaries with the most common settings or take these dictionaries and apply the contained settings. These can be used to easily store and re-apply device configuration within a script.

Additionally, there is `get_full_info` method, which returns as complete information as possible. It is particularly useful to check the device status and see if it is connected and working properly, and to save the devices configuration when acquiring the data. Finally, the settings can also be accessed through `.dv` attribute, which provides dictionary-like interface:

```

>>> wheel = Thorlabs.FW("COM1") # connect to FW102 motorized filter wheel
>>> wheel.get_position()
1
>>> wheel.get_settings()
{'pcount': 6,
 'pos': 1,
 'sensors_mode': 'off',
 'speed_mode': 'high',
 'trigger_mode': 'in'}
>>> wheel.dv["pos"]
1
>>> wheel.apply_settings({"pos":2})
>>> wheel.get_position()
2
>>> wheel.dv["pos"] = 3

```

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```
>>> wheel.get_position()
3
>>> wheel.close()
```

By default not all information is shown, as it can take long time (up to several seconds) to obtain it, and it takes a lot of space on the screen. To get a full set of parameters, you can call `get_full_info("all")`:

```
>> cam = IMAQdx.IMAQdxCamera()
>> cam.get_full_info()
{  'roi': (0, 1312, 0, 1082),
   'acquisition_in_progress': False,
   'frames_status': TFramesStatus(acquired=0, unread=0, skipped=0, buffer_size=0),
   'cls': 'IMAQdxCamera',
   'conn': 'cam0',
   'detector_size': (1312, 1082),
   'device_info': TDeviceInfo(vendor='Photonfocus AG', model='HD1-D1312-80-G2-12',
↳ serial_number='000000000000000000', bus_type='Ethernet')  }
>>
>> cam.get_full_info("all")
{  'roi': (0, 1312, 0, 1082),
   'acquisition_in_progress': False,
   'frames_status': TFramesStatus(acquired=0, unread=0, skipped=0, buffer_size=0),
   'camera_attributes': Dictionary('AcquisitionAttributes/AdvancedEthernet/
↳ BandwidthControl/ActualPeakBandwidth': 1000.0
   ... lots and lots of attributes
   'OffsetX': 0
   'OffsetY': 0
   'PayloadSize': 1419584
   'PixelFormat': Mono8
   'Width': 1312),
   'cls': 'IMAQdxCamera',
   'conn': 'cam0',
   'detector_size': (1312, 1082),
   'device_info': TDeviceInfo(vendor='Photonfocus AG', model='HD1-D1312-80-G2-12',
↳ serial_number='000000000000000000', bus_type='Ethernet')  }
```

## Dependencies and external software

Many devices require external software not provided with this package.

The simpler devices using serial connection (either with an external USB-to-Serial adapter, or with a similar built-in chip) only need the corresponding drivers: either standard adapter drivers or the ones supplied by the manufacturer, e.g., via Thorlabs APT software. If the device already shows up as a serial communication port in the OS, no additional software is normally needed. Similarly, devices using Ethernet connection do not need any external software, as long as they are properly connected to the network. Finally, devices using Visa connection require NI VISA Runtime, which is freely available from the [National Instruments website](#). See also [PyVISA documentation](#) for details.

Devices which require manufacturer DLLs are harder to set up. For most of them, at the very least, you need to install the manufacturer-provided software for communication. Frequently it already includes the necessary libraries, which means that nothing else is required. However, sometimes you would need to download either an additional SDK package, or DLLs directly from the website. Since these libraries take a lot of space and are often proprietary, they are not distributed with the pylablib.

Note that DLLs can have 32-bit and 64-bit version, and this version should agree with the Python version that you use. Unless you have a really good reason to do otherwise, it is strongly recommended to use 64-bit Python, which means that you would need 64-bit DLLs, which is the standard in most cases these days. To check your Python bitness, you can read the prompt when running the Python console, or run `python -c "import platform; print(platform.architecture()[0])"` in the command line.

In addition, you need to provide pylablib with the path to the DLLs. In many cases it checks the standard locations such as the default System32 folder (used, e.g., in DCAM or IMAQ cameras), paths contained on the PATH environment variable, or defaults paths for manufacturer software (such as C:/Program Files/Andor SOLIS for Andor cameras). If the software path is different, or if you choose to obtain DLLs elsewhere, you can also explicitly provide path by setting the library parameter:

```
import pylablib as pll
pll.par["devices/dlls/andor_sdk3"] = "D:/Program Files/Andor SOLIS"
from pylablib.devices import Andor
cam = Andor.AndorSDK3Camera()
```

All of these requirements are described in detail for the specific devices.

Starting from Python 3.8 the DLL search path is changed to not include the files contained in PATH environment variable and in the script folder. By default, this behavior is still emulated when pylablib searches for the DLLs, since it is required in some cases (e.g., Photon Focus pfcam interface). If needed, it can be turned off (i.e., switched to the new default behavior of Python 3.8+) by setting `pll.par["devices/dlls/add_environ_paths"]=False`.

## Advanced examples

Connecting to a Cryomagnetics LM500 level meter and reading out the level at the first channel:

```
from pylablib.devices import Cryomagnetics # import the device library
with Cryomagnetics.LM500("COM1") as lm:
    level = lm.get_level(1) # read the level
```

Stepping the M Squared laser wavelength and recording an image from the Andor iXon camera at each step:

```
with M2.Solstis("192.168.1.2", 34567) as laser, Andor.AndorSDK2Camera() as cam: #_
    ↳connect to the devices
    # change some camera parameters
    cam.set_exposure(50E-3)
    cam.set_roi(0, 128, 0, 128, hbin=2, vbin=2)
    cam.setup_shutter("open")
    # start camera acquisition
    wavelength = 770E-9 # initial wavelength (in meters)
    images = []
    cam.start_acquisition()
    while wavelength < 780E-9:
        laser.coarse_tune_wavelength(wavelength) # tune the laser frequency (using_
        ↳coarse tuning)
        time.sleep(0.5) # wait until the laser stabilizes
        cam.wait_for_frame() # ensure that there's a frame in the camera queue
        img = cam.read_newest_image()
        images.append(img)
        wavelength += 0.5E-9
```

## Available devices

- *Cameras*
  - *Andor SDK2* and *Andor SDK3*: variety of Andor (currently part of Oxford Instruments) cameras. Tested with Andor iXon, Luca, Newton, Zyla, Neo and Marana.
  - *Allied Vision Bonito* cameras: CameraLink-interfaced cameras. Tested with Bonito CL-400B/C and NI IMAQ frame grabber.
  - *Basler*: Basler pylon-compatible cameras. Tested with an emulated Basler camera.
  - *BitFlow*: BitFlow Axion family frame grabbers. Tested with BitFlow Axion 1xB frame grabber together with PhotonFocus MV-D1024E camera.
  - *DCAM*: Hamamatsu cameras. Tested with Hamamatsu Orca Flash 4.0 and ImagEM.
  - *NI IMAQ*: National Instruments frame grabbers. Tested with NI PCI-1430 and PCI-1433 frame grabbers together with PhotonFocus MV-D1024E camera.
  - *NI IMAQdx*: National Instruments universal camera interface. Tested with Ethernet-connected PhotonFocus HD1-D1312 camera.
  - *Photon Focus*: Photon Focus pfcam interface. Tested with PhotonFocus MV-D1024E camera connected through either NI frame grabbers (PCI-1430 and PCI-1433) or Silicon Software frame grabbers (microEnable IV AD4-CL).
  - *PCO SC2*: PCO cameras. Tested with pco.edge cameras with CLHS and regular CameraLink interfaces, and with pco.pixelfly usb cameras.
  - *Picam*: Princeton Instruments cameras. Tested with a PIXIS 400 camera.
  - *PVCAM*: Photometrics cameras. Tested with a Prime 95B camera.
  - *Silicon Software*: Silicon Software frame grabbers. Tested with microEnable IV AD4-CL frame grabbers together with PhotonFocus MV-D1024E camera.
  - *Thorlabs Scientific Cameras*: Thorlabs sCMOS cameras. Tested with Thorlabs Kiralux camera.
  - *Uc480/uEye*: multiple cameras, including simple Thorlabs and IDS cameras. Tested with IDS SC2592R12M and Thorlabs DCC1545M.
  - *Mightex*: several different USB camera types with different APIs. Implemented and tested only for S-series cameras.
- *Stages*
  - *Attocube ANC300* and *Attocube ANC350*: most common Attocube positioner controllers. Tested with Ethernet and USB connection for ANC300, and USB connection for ANC350.
  - *Thorlabs APT/Kinesis*: basic Thorlabs motorized stages and optomechanics devices. Tested with KDC101, K10CR1, and BSC201 motor controllers, KIM101 piezo motor controller, KPZ101 piezo controllers, as well as MFF101 and FW102 (described at a [different page](#))
  - *Thorlabs Elliptec*: resonant piezoelectric Thorlabs stages. Tested with ELL18 and ELL14 rotational mounts.
  - *Newport Picomotor*: precision piezo-actuated screws based on slip-stick principle. Tested with Newport 8742 Picomotor driver using Ethernet or USB connection.
  - *Arcus Performax*: fairly common single- and multi-axis motor controllers sold under different brands: Arcus, Nippon Pulse America, or Newmark Systems. Tested with PMX-4EX device with USB connection.
  - *Trinamic*: universal motor controllers and drivers. Tested with a single-axis TMCM-1110 controller with USB connection.

- *Standa*: Standa motorized positioners. Tested with a 8SMC4-USB single-axis controller and 8MT167-25 stepper motor stage.
- *SmarAct*: high-performance piezo sliders. Currently simple open-loop *SCU controllers* and *MCS2 controllers* are supported. Tested with a standard HCU controller unit and an MCS2 controller with several SLx stages.
- *Physik Instrumente*: piezo controllers. So far only PI E-515 and PI E-516 is supported and tested.
- *Basic sensors*
  - *HighFinesse*: laser wavelength meters. Tested with WS6 and WS7 USB-controlled devices.
  - *Ophir*: optical power and energy meters. Tested with Ophir Vega.
  - *Thorlabs*: optical power and energy meters. Tested with PM160.
  - *Lakeshore*: temperature sensors. Tested with Lakeshore 218.
  - *Cryocon*: temperature sensors. Tested with CryoCon 14C.
  - *Cryomagnetics*: liquid nitrogen or helium level sensor. Tested with LM-500 and LM-510 sensors.
  - *Pfeiffer*: pressure gauges. Tested with TPG261 and DPG202 controllers.
  - *Leybold*: pressure gauges. Tested with ITR90 gauge.
  - *Kurt J. Lesker*: pressure gauges. Tested with KJL300 gauge.
  - *Agilent*: pressure gauges. Tested with XGS-600 controller and FRG700 gauge.
  - *Thorlabs quadrature detector controller*. Tested with TPA101.
  - *Keithley multimeters*. Tested with model 2110.
  - *Voltcraft multimeters*. Tested with VC-7055BT and VC880.
- *Lasers*
  - *Basic lasers*
    - \* *Lighthouse Photonics SproutG*
    - \* *Laser Quantum Finesse*
  - *M2 Solstis laser and external mixing module*
  - *Toptica iBeam Smart laser*
  - *Hubner Cobolot*
  - *Sirah Matisse laser*
  - *NKT Photonics lasers*
- *Tektronix oscilloscopes*. Tested with TDS2002B, TDS2004B, and DPO2004B.
- *NI DAQs*. Tested with NI USB-6008, NI USB-6343, and NI PCIe-6323.
- *Generic AWGs*. Tested with Agilent 33500 and 33220A, Rigol DG1022, Tektronix AFG1022, GW Instek AFG2225 and AFG2115, and RS Comp AFG21005.
- *Andor spectrographs*. Tested with Kymera 328i spectrograph connected via an Andor Newton camera through I2C interface.
- *Miscellaneous Thorlabs devices*: *MFF101/102* motorized flip mirror mount, *FW102/212* motorized filter wheel, and *MDT693/694* high-voltage source.

- *Miscellaneous OZOptics devices*: *EPC04* fiber polarization controller, *DD100* motorized fiber attenuator, and *TF100* motorized fiber filter.
- *Lumel devices*: *RE72* temperature controller
- *Miscellaneous devices*
  - *Conrad relay board*
  - *Basic Arduino communication*
  - *ElektroAutomatik power supplies*
  - *Rigol power supplies*
- *Generic Windows devices*
- *Mid-level protocols*
  - *Modbus*

## 2.2.2 Cameras

Basic concepts are described at the [cameras communication page](#).

Currently supported cameras:

- *Andor SDK2* and *Andor SDK3*: variety of Andor (currently part of Oxford Instruments) cameras. Tested with Andor iXon, Luca, Newton, Zyla, Neo and Marana.
- *Allied Vision Bonito* cameras: CameraLink-interfaced cameras. Tested with Bonito CL-400B/C and NI IMAQ frame grabber.
- *Basler*: Basler pylon-compatible cameras. Tested with an emulated Basler camera.
- *BitFlow*: BitFlow Axion family frame grabbers. Tested with BitFlow Axion 1xB frame grabber together with PhotonFocus MV-D1024E camera.
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- *PVCAM*: Photometrics cameras. Tested with a Prime 95B camera.
- *Silicon Software*: Silicon Software frame grabbers. Tested with microEnable IV AD4-CL frame grabbers together with PhotonFocus MV-D1024E camera.
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- *Mightex*: several different USB camera types with different APIs. Implemented and tested only for S-series cameras.

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**Note:** General device communication concepts are described on the corresponding [page](#).

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## Cameras control basics

### Basic examples

Basic camera usage is fairly straightforward:

```
from pylablib import Andor
cam = Andor.AndorSDK3Camera() # connect to the camera
cam.set_exposure(10E-3) # set 10ms exposure
cam.set_roi(0,128,0,128) # set 128x128px ROI in the upper left corner
images = cam.grab(10) # grab 10 frames
cam.close()
```

In case you need to grab and process frames continuously, the example is a bit more complicated:

```
with Andor.AndorSDK2Camera() as cam: # to close the camera automatically
    cam.start_acquisition() # start acquisition (automatically sets it up as well)
    while True: # acquisition loop
        cam.wait_for_frame() # wait for the next available frame
        frame=cam.read_oldest_image() # get the oldest image which hasn't been read yet
        # ... process frame ...
```

Some concepts are explained below in more detail.

## Basic concepts

### Frames buffer

In most cases, the frames acquired by the camera are first temporarily stored in the local camera and / or frame grabber memory, from which they are transferred to the PC RAM by the camera drivers. Afterwards, this memory is made available to all other applications. In principle, it should be enough to store only the most recent frame in RAM, and for the user software to continuously wait for a new frame, immediately read it from RAM and process it. However, such approach is very demanding to the user code: if the new frame is acquired before the previous one is processed or copied, then the RAM data is overwritten, and the old frame is lost. Hence, it is more practical to have a *buffer* of several most recently acquired frames to account for inevitable interruptions in the user wait-read-process loop caused by OS scheduling and by other jobs. In this case, the frames get lost only when the buffer is completely filled, and the oldest frames starts getting overwritten.

When using the camera classes provided by pylablib, you do not need to worry about setting up the buffer yourself, since it is done behind the scene either by the manufacturer's code or by the device class. However, it is important to keep in mind the existence of the buffer when setting up the acquisition, interpreting the buffer and acquired frames status, or identifying the skipped frames.

The size of the buffer can almost always be selected by the user. Typically it is a good idea to have at least 100ms worth of frames there, although, depending on the other jobs performed by the software, it can be larger.



## Acquisition setup

Setting up an acquisition process might take a lot of time (up to 10s in more extreme cases). This happens mostly because of the buffer allocation and setting up internal API structures; initiating the acquisition process itself is fairly fast. Hence, it is useful to separate setting up / cleaning up and starting / stopping.

The first two procedures correspond to `setup_acquisition` and `clear_acquisition` method, which are slow, but rarely called. Usually, they only need to be invoked right after connecting to the camera, or when the acquired image size is changed (e.g., due to a change in binning or ROI). Since these methods deal with buffer allocation, in almost all cases they take a parameter specifying buffer size (typically called `nframes`).

The other two procedures correspond to `start_acquisition` and `stop_acquisition` methods. These try to be as fast as possible, as they need to be called any time the acquisition is started or stopped, or when minor parameters (frame rate, exposure, trigger mode) are called.

## Region of interest (ROI) and binning

Most cameras allow the user to select only a part of the whole sensor for readout and transfer. Since the readout speed is usually the factor limiting the frame rate, selecting smaller ROI frequently lets you achieve higher frame rate. In addition, it also reduces the size of the frame buffer and the data transfer load. Same goes for binning: many cameras can combine values of several consecutive pixels in the same row or column (or both), which results in smaller images and, depending on the camera architecture, higher signal-to-noise ratio compared to binning in post-processing. Much less frequently you can set up subsampling instead of binning, which skips pixels instead of averaging them together.

Both operations depend very strongly on the exact hardware, so there are typically many associated restriction. The most common are minimal sizes in width and height, positions and sizes being factors of some power of 2 (up to 32 for some cameras), or equal binning for both axes. Device classes will typically round the ROI to the nearest allowed value. Furthermore, the scaling of the maximal frame rate with the ROI size is also hardware-dependent; for example, in many sCMOS chips readout speed only depends on the vertical extent, since the readout is done simultaneously for the whole row. In most cases, it takes some experiments to get a hang of the camera behavior.

## Exposure and frame rate

Almost all scientific cameras let user change the exposure, typically in a wide range (down to sub-ms). Frequently they also allow to separately change the frame period (inverse of the frame rate). Usually (but not always) the minimal frame period is set by the exposure plus some readout time, which depends on the ROI and some additional parameters such as pixel clock or simultaneous readout mode. Usually exposure takes priority over the frame period, i.e., if the frame period is set too short, it is automatically adjusted. Notable exception from this rule is [Uc480](#) interface, where this dependence is reversed.

## Triggering

Usually the cameras will have several different options for triggering, i.e., choosing when to start acquiring a new frame or a new batch of frames. The default option is the internal trigger, which means that the internal timer generates trigger event at a constant rate (frame rate). Many cameras will also take an external trigger signal to synchronize acquisition to external events or other cameras. Typically, a rising edge from 0 to 5V on the input will initiate the frame acquisition, but more exotic options (different polarities or levels, exposure control with pulse width, line-readout trigger) can be present.



## Application notes and examples

Here we talk more practically about performing tasks common to most cameras.

### Simple acquisition

Frame acquisition is, understandably, the most important part of the camera. Basic acquisition can be done without explicitly setting up the acquisition loop, simply by using `ICamera.snap()` and `ICamera.grab()` methods which, correspondingly, grab a single frame or a given number of frames:

```
from pylablib import Andor
cam = Andor.AndorSDK3Camera() # connect to the camera
img = cam.snap() # grab a single frame
images = cam.grab(10) # grab 10 frames (return a list of frames)
cam.close()
```

These allow for quick tests of whether the camera works properly, and for occasional frames acquisition. However, these methods have to start and stop acquisition every time they are called, which for some cameras can take about a second. Hence, if continuous acquisition and high frame rate are required, you would need to set up the acquisition loop.

### Acquisition loop

A typical simple acquisition loop has already been shown above:

```
# nframes=100 relates to the size of the frame buffer; the acquisition will continue_
↳ indefinitely
cam.setup_acquisition(mode="sequence", nframes=100) # could be combined with start_
↳ acquisition, or kept separate
cam.start_acquisition()
while True: # acquisition loop
    cam.wait_for_frame() # wait for the next available frame
    frame = cam.read_oldest_image() # get the oldest image which hasn't been read yet
    # ... process frame ...
    if time_to_stop:
        break
cam.stop_acquisition()
```

It relies on 3 sets of methods. First, starting and stopping acquisition using `start_acquisition` and `stop_acquisition`. As explained above, one also has an option to setup the acquisition first using `setup_acquisition`, which makes the subsequent `start_acquisition` call faster. However, one can also supply the same setup parameters to `start_acquisition` method, which automatically sets up the acquisition if it is not set up yet, or if any parameters are different from the current ones.

Second are the methods for checking on the acquisition process. The method used above is `wait_for_frame`, which by default waits until there is at least one unread frame in the buffer (i.e., it exits immediately if there is already a frame available). Its arguments modify this behavior by changing the point from which the new frame is acquired (e.g., from the current call), or the minimal required number of frames. Alternatively, there is a method `get_new_images_range`, which returns a range of the frame indices which have been acquired but not read. This method allows for a quick check of a number of unread frames without pausing the acquisition.

Finally, there are methods for reading out the frames. The simplest method is `read_oldest_image`, which return the oldest image which hasn't been read yet, and marks it as read. A more powerful is the `read_multiple_images`

method, which can return a range of images (by default, all unread images). Both of these methods also take a `peek` argument, which allows one to read the frames without marking them as read.

## Returned frame format

`ICamera.read_multiple_images()` method described above has several different formats for returning the frames, which can be controlled using `ICamera.set_frame_format()` and checked `ICamera.get_frame_format()`. The default format is "list", which returns a list of individual frames. The second possibility is "array", which returns a single 3D numpy array with all the frames. Finally, "chunks" returns a list of 3D arrays, each containing several consecutive frames.

While "chunks" format is the hardest to work with, it provides the best performance. First, it does not require any extra memory copies, which negatively affect performance at very high data rates, above ~1Gb/s. Second, it can combine multiple small frames together into a single array, which makes further processing faster, as it does not require explicit Python loop over every frame. This usually becomes important at frames rates above ~10kFPS, where treating each frame as an individual 2D array leads to significant overhead.

## Frame indexing

Different areas and libraries adopt different indexing convention for 2D arrays. The two most common ones are coordinate-like `xy` (the first index is the `x` coordinate, the second is `y` coordinate, and the origin is in the lower left corner) and matrix-like `ij` (the first index is row, the second index is column, the origin is in the upper right corner). Almost all cameras adopt the `ij` convention. The only exception is Andor SDK2, which uses similar row-column indexing, but counting from the bottom.

By default, the frames returned by the camera are indexed in the preferred convention, to reduce the overhead on re-indexing the frames. It is possible to check and change it using `ICamera.get_image_indexing()` and `ICamera.set_image_indexing()` methods:

```
>> cam.set_roi(0,256,0,128) # 256px horizontally, 128 vertically
>> cam.snap().shape # 128 rows, 256 columns
(128, 256)
>> cam.set_image_indexing("xyb") # standard xy indexing, starting from the bottom
>> cam.snap().shape
(256, 128)
```

## ROI, detector size and frame shape

Both ROI and binning are controlled by one pair of methods `get_roi` and `set_roi` which, depending on whether camera supports binning, take (and return) 4 or 6 arguments: start and stop positions of ROI along both axes and, optionally, binning along the axes:

```
cam.set_roi(0,128,0,256) # set 128x256px (width x height) ROI in the (typically) upper_
↳left controller
cam.set_roi(0,128) # set roi with 128px width and full height (non-supplied arguments_
↳take extreme values)
cam.set_roi(0,128,0,128,2,2) # set 128x128px ROI with 2x2 binning; the resulting image_
↳size is 64x64
```

Regardless of the frame indexing, the first pair of arguments always controls horizontal span, the second pair controls vertical span, and the last pair controls horizontal and vertical binning (if applicable).

In addition, there is a couple of methods to acquire the detector and frame size. The first method is `get_detector_size`. It always returns the full camera detector size as a tuple (width, height) and, therefore, is not affected by ROI, binning, and indexing. The second method is `get_data_dimensions`, which returns the shape of the returned frame given the currently set up indexing. The results of this method do depend on the ROI, binning, and indexing:

```
>> cam.get_detector_size() # (width, height)
(2560, 1920)
>> cam.get_data_dimensions() # (rows, columns), i.e., (height, width)
(1920, 2560)

>> cam.set_roi(0,256,0,128,2,2) # 256px horizontally, 128 vertically, 2x2 binning
>> cam.get_detector_size() # unaffected
(2560, 1920)
>> cam.get_data_dimensions() # depends on ROI
(64, 128)

>> cam.set_image_indexing("xyb")
>> cam.get_detector_size() # unaffected
(2560, 1920)
>> cam.get_data_dimensions() # depends on indexing
(128, 64)
```

## Exposure and frame period

In pylablib these parameters are normally controlled by `get_exposure/set_exposure` and, correspondingly `get_frame_period/set_frame_period` methods. In addition, `get_frame_timings` method provides an overview of all the relevant times. Exposure typically takes priority over frame period: if the frame period is set too small, it becomes the smallest possible for the given exposure; at the same time, if the exposure is set too big, it is still applied, and the frame period becomes the smallest possible with this exposure:

```
>> cam.get_frame_timings() # frame period is a usually bit larger due to the readout,
    ↳time
TAcqTimings(exposure=0.1, frame_period=0.12)

>> cam.set_exposure(0.01)
>> cam.get_frame_timings() # smaller exposure is still compatible with this frame period
TAcqTimings(exposure=0.01, frame_period=0.12)

>> cam.set_frame_period(0) # effectively means "set the highest possible frame rate"
>> cam.get_frame_timings()
TAcqTimings(exposure=0.01, frame_period=0.03)

>> cam.set_exposure(0.2)
>> cam.get_frame_timings() # frame period is increased accordingly
TAcqTimings(exposure=0.2, frame_period=0.22)
```

There are exceptions for some camera types, which are discussed separately.

## Camera attributes

Some camera interfaces, e.g., *Thorlabs Scientific Cameras*, *PCO SC2*, or *NI IMAQ* are fairly specific, and only apply to a handful of devices with very similar capabilities. In this case, pylablib usually attempts to implement as much of the functionality as possible given the available hardware, and to present it via the camera object methods.

In other cases, e.g., *NI IMAQdx*, *Andor SDK3*, or *DCAM*, the same interface deals with many fairly different cameras. This is especially true for IMAQdx, which covers hundreds of cameras from dozens of manufacturers, all with very different capabilities and purpose. Since managing such cameras can not usually be conformed to a small set of functions, it is implemented through camera attributes mechanism. That is, for each camera the interface defines a set of attributes (sometimes also called properties or features), which can be queried or set by their names, and whose exact meaning and possible values depend on the specific camera.

Typically, cameras dealing with attributes will implement `IAttributeCamera.get_attribute_value()` and `IAttributeCamera.set_attribute_value()` for querying and setting the attributes, as well as dictionary-like `.cav` (stands for “camera attribute value”) interface to do the same thing:

```
>> cam = Andor.AndorSDK3Camera()
>> cam.get_attribute_value("CameraAcquiring") # check if the camera is acquiring
0
>> cam.set_attribute_value("ExposureTime", 0.1) # set the exposure to 100ms
>> cam.cav["ExposureTime"] # get the exposure; could also use cam.get_attribute_value(
↪ "ExposureTime")
0.1
```

Additionally, there are `IAttributeCamera.get_all_attribute_values()` and `IAttributeCamera.set_all_attribute_values()` which get and set all camera attributes (possibly only within the given branch, if camera attributes form a hierarchy). Finally, methods `IAttributeCamera.get_attribute()` and `IAttributeCamera.get_all_attributes()`, together with the corresponding `.ca` interface, allow to query specific attribute objects, which provide additional information about the attributes: whether they are writable or readable, their range, description, possible values, types, etc.:

```
>> cam = DCAM.DCAMCamera()
>> attr=cam.ca["EXPOSURE TIME"] # get the exposure attribute
DCAMAttribute(name='EXPOSURE TIME', id=2031888, min=0.001, max=10.0, unit=1)
>> attr.max
10.0
>> attr.set_value(0.1) # same as cam.set_attribute_value("EXPOSURE TIME", 0.1)
```

Note that, depending on the camera, the attribute properties (especially minimal and maximal value) can depend on the other camera attributes. For example, minimal exposure can depend on the frame size:

```
>> cam = DCAM.DCAMCamera()
>> attr=cam.ca["EXPOSURE TIME"] # get the exposure attribute
DCAMAttribute(name='EXPOSURE TIME', id=2031888, min=0.001, max=10.0, unit=1)
>> attr.min
0.001
>> cam.set_roi(0, 0, 0, 0) # set the minimal possible ROI
(0, 4, 0, 4, 1, 1)
>> attr.min # minimal value hasn't been updated yet
0.001
>> attr.update_limits() # update the property limits
>> attr.min # now the minimal possible exposure is smaller
7.795e-05
```

If the documentation is not available (as is the case for, e.g., some IMAQdx cameras), the best way to learn about the attributes is to use the native software (whenever available) to modify camera settings and then check how the attributes change. Besides that, it is always useful to check attribute description (available for IMAQdx parameter), their range, and the available values for enum attributes.

## Trigger setup

The trigger is usually set up using `set_trigger_mode` method, although it might be different if more specialized modes are used. When external trigger is involved, most of the code (such as acquisition set up and start) stays the same. The only difference is the rate at which the frames are generated:

```
frame = cam.snap() # starts acquiring immediately, returns after a single frame
cam.set_trigger_mode("ext") # set up the trigger mode
frame = cam.snap()
# after cam.snap() is called, the execution will wait
# for an external trigger pulse to acquire the frame and return
```

## Frame metainfo

Many cameras supply additional information together with the frames. Most frequently it contains the internal frames-tamp and timestamp (which are useful for tracking missing frames), but sometimes it also includes additional information such as frame size or location, status, or auxiliary input bits. To get this information, you can supply the argument `return_info=True` to the `read_multiple_images` method. In this case, instead of a single list of frames, it will return a tuple of two lists, where the second list contains this metainfo.

There are several slightly different metainfo formats, which can be set using `ICamera.set_frame_info_format()` method. The default representation is a (possibly nested) named tuple, but it is also possible to represent it as a flat list, flat dictionary, or a numpy array. The exact structure and values depend on the camera.

Keep in mind, that for some camera interfaces (e.g., *Uc480* or *Silicon Software*) obtaining the additional information might take relatively long, even longer than the proper frame readout. Hence, at higher frame rates it might become a bottleneck, and would need to be turned off.

## Related projects

Pylabelib [cam-control](#) is a standalone software package which builds on camera classes included in pylablib. It provides an easy way to detect and control many different cameras and acquire their data. In addition, it supports custom on-line image processing, flexible data acquisition, and control by external software using a TCP/IP server.

## Currently supported cameras

- *Andor SDK2* and *Andor SDK3*: variety of Andor (currently part of Oxford Instruments) cameras. Tested with Andor iXon, Luca, Newton, Zyla, Neo and Marana.
- *Allied Vision Bonito* cameras: CameraLink-interfaced cameras. Tested with Bonito CL-400B/C and NI IMAQ frame grabber.
- *Basler*: Basler pylon-compatible cameras. Tested with an emulated Basler camera.
- *BitFlow*: BitFlow Axion family frame grabbers. Tested with BitFlow Axion 1xB frame grabber together with PhotonFocus MV-D1024E camera.
- *DCAM*: Hamamatsu cameras. Tested with Hamamatsu Orca Flash 4.0 and ImagEM.

- *NI IMAQ*: National Instruments frame grabbers. Tested with NI PCI-1430 and PCI-1433 frame grabbers together with PhotonFocus MV-D1024E camera.
- *NI IMAQdx*: National Instruments universal camera interface. Tested with Ethernet-connected PhotonFocus HD1-D1312 camera.
- *Photon Focus*: Photon Focus pfcam interface. Tested with PhotonFocus MV-D1024E camera connected through either NI frame grabbers (PCI-1430 and PCI-1433) or Silicon Software frame grabbers (microEnable IV AD4-CL).
- *PCO SC2*: PCO cameras. Tested with pco.edge cameras with CLHS and regular CameraLink interfaces, and with pco.pixelfly usb cameras.
- *Picam*: Princeton Instruments cameras. Tested with a PIXIS 400 camera.
- *PVCAM*: Photometrics cameras. Tested with a Prime 95B camera.
- *Silicon Software*: Silicon Software frame grabbers. Tested with microEnable IV AD4-CL frame grabbers together with PhotonFocus MV-D1024E camera.
- *Thorlabs Scientific Cameras*: Thorlabs sCMOS cameras. Tested with Thorlabs Kiralux camera.
- *Uc480/uEye*: multiple cameras, including simple Thorlabs and IDS cameras. Tested with IDS SC2592R12M and Thorlabs DCC1545M.
- *Mightex*: several different USB camera types with different APIs. Implemented and tested only for S-series cameras.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Andor cameras

Andor implements two completely separate interfaces for different cameras. The older one, called SDK2, or simply SDK, provides interface for the older cameras: iXon, iKon, iStart, iDus, iVac, Luca, Newton. The details of this SDK are available in the [manual](#).

The newer SDK, called SDK3, covers newer cameras: Zyla, Neo, Apogee, Sona, Marana, and Balor. The [manual](#) describes the cameras and capabilities in more details.

The required DLLs are distributed with [Andor Solis](#) or the corresponding [Andor SKD](#). In most cases, you have Andor Solis already installed to provide the drivers and to communicate with the cameras to begin with.

## Andor SDK 2

This is an older SDK, which mainly involves older cameras. It has been tested with Andor iXon, Luca, and Newton.

The code is located in `pylablib.devices.Andor`, and the main camera class is `pylablib.devices.Andor.AndorSDK2Camera`.

## Software requirements

The required DLL can have different names depending on the Solis version and SDK bitness. For 64-bit version it will be called `atmcd64d.dll` or `atmcd64d_legacy.dll`. For 32-bit version, correspondingly, `atmcd32d.dll` or `atmcd32d_legacy.dll`. By default, library searches for DLLs in Andor Solis and Andor SDK folder in Program Files folder (or Program files (x86), if 32-bit version of Python is running), as well as in the folder containing the script. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/andor_sdk2`:

```
import pylablib as pll
pll.par["devices/dlls/andor_sdk2"] = "path/to/dlls"
from pylablib.devices import Andor
cam = Andor.AndorSDK2Camera()
```

## Connection

The cameras are identified by their index, starting from zero. To get the total number of cameras, you can run `Andor.get_cameras_number_SDK2`:

```
>> from pylablib.devices import Andor
>> Andor.get_cameras_number_SDK2()
2
>> cam1 = Andor.AndorSDK2Camera(idx=0)
>> cam2 = Andor.AndorSDK2Camera(idx=1)
>> cam1.close()
>> cam2.close()
```

**Warning:** It is important to close all camera connections before finishing your script. Otherwise, DLL resources might become permanently blocked, and the only way to solve it would be to restart the PC.

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- Since the manufacturer DLLs do not provide methods to get most of the camera parameters (such as exposure or ROI), it is impossible to know them when connecting the camera. To get around it, the camera is put into a “default” state any time the connection is opened.
- When applicable, it is important to properly set the cooling setpoint and the fan mode. By default, the fan is turned off, and the cooling is set to the 20<sup>th</sup> percentile of the whole range (e.g., -80C for Andor iXon). It is possible to pass these parameters on camera creation:

```
cam = Andor.AndorSDK2Camera(temperature=-50, fan_mode="on")
```

- Often cameras have a lot of different readout parameters: channel, amplifier, vertical and horizontal scan speed, etc. These parameters greatly affect the camera sensitivity and readout speed. Upon the connection, the parameter are typically set to the slowest mode. To get the list of all possible parameter combinations, you can use `AndorSDK2Camera.get_all_amp_modes()` and `AndorSDK2Camera.get_max_vsspeed()`. Afterwards, you can set them using `AndorSDK2Camera.set_amp_mode()` and `AndorSDK2Camera.set_vsspeed()`.



- The default shutter parameter is "closed". This preserves camera from possible high illumination, but can lead to confusion, if you expect to see some image.
- This SDK does not allow for specifying number of frames in the frames buffer. However, the parameters chosen by the SDK are usually reasonable (at least a second worth of acquisition).
- Some cameras (e.g., iXon) have lots of readout (full frame, ROI, full vertical binning, etc.) and acquisition modes (single, continuous, accumulating, kinetic cycle, etc.). They are described in details in the [manual](#).

## Andor SDK 3

This is a newer SDK, which covers the newer cameras. It has been tested with Andor Zyla, Neo and Marana.

The code is located in `pylablib.devices.Andor`, and the main camera class is `pylablib.devices.Andor.AndorSDK3Camera`.

## Software requirements

This library requires several DLLs all located in the same folder: `atcore.dll`, `atblkbx.dll`, `atcl_bitflow.dll`, `atdevapogee.dll`, `atdevregcam.dll`, `atusb_libusb.dll`, `atusb_libusb10.dll`. Same as for SDK2, pylablib looks for DLLs in Andor Solis and Andor SDK3 folders in Program Files folder (or Program files (x86), if 32-bit version of Python is running), as well as in the folder containing the script. A custom DLLs path can be specified using the library parameter `devices/dlls/andor_sdk3`:

```
import pylablib as pll
pll.par["devices/dlls/andor_sdk3"] = "path/to/SDK3/dlls"
from pylablib.devices import Andor
cam = Andor.AndorSDK3Camera()
```

## Connection

The cameras are identified by their index, starting from zero. To get the total number of cameras, you can run `Andor.get_cameras_number_SDK3`:

```
>> from pylablib.devices import Andor
>> Andor.get_cameras_number_SDK3()
2
>> cam1 = Andor.AndorSDK3Camera(idx=0)
>> cam2 = Andor.AndorSDK3Camera(idx=1)
>> cam1.close()
>> cam2.close()
```



## Operation

The operation of these cameras is also relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- The SDK also provides a universal interface for getting and setting various *camera attributes* (called “features” in the documentation) using their name. You can use `AndorSDK3Camera.get_attribute_value()` and `AndorSDK3Camera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = Andor.AndorSDK3Camera()
>> cam.get_attribute_value("CameraAcquiring") # check if the camera is acquiring
0
>> cam.set_attribute_value("ExposureTime", 0.1) # set the exposure to 100ms
>> cam.cav["ExposureTime"] # get the exposure; could also use cam.get_attribute_
    ↪ value("ExposureTime")
0.1
```

Some values serve as commands; these can be invoked using `AndorSDK3Camera.call_command()` method. To see all available attributes, you can call `AndorSDK3Camera.get_all_attributes()` to get a dictionary with attribute objects, and `AndorSDK3Camera.get_all_attribute_values()` to get the dictionary of attribute values. The attribute objects provide additional information: their kind, whether they are implemented, readable, or writable, what are their limits or possible values, etc:

```
>> cam = Andor.AndorSDK3Camera()
>> attr = cam.get_attribute("SensorTemperature")
>> attr.readable
True
>> attr.writable
False
>> (attr.min, attr.max)
(-100.0, 50.0)
```

The description of the attributes is given in [manual](#).

- USB cameras can, in principle, generate data at higher rate than about 320Mb/s that the USB3 bus supports. For example, Andor Zyla with 16 bit readout has a single full frame size of 8Mb, which puts the maximal USB throughput at about 40FPS. At the same time, the camera itself is capable of reading up to 100FPS at the full frame. Hence, it is possible to overflow the camera internal buffer (size on the order of 1Gb) regardless of the PC performance. If this happens, the acquisition process halts and needs to be restarted. You can check the number of buffer overflows using `AndorSDK3Camera.get_missed_frames_status()`, and reset this counter using `AndorSDK3Camera.reset_overflows_counter()`; the counter is also automatically resets on acquisition clearing, but not stopping.

Furthermore, the class implements different strategies when encountering overflow while waiting for a new frame. The specific strategy is selected using `AndorSDK3Camera.set_overflow_behavior()`, and it can be "error" (raise `AndorFrameTransferError`, which is the default behavior), "restart" (restart the acquisition and immediately raise timeout error), or "ignore" (ignore the overflow, which will eventually lead to a timeout error, as the new frames are no longer generated).

---

**Note:** General camera communication concepts are described on the corresponding [page](#).

---

## Allied Vision Bonito cameras

Allied Vision manufactures a variety of cameras with different interfaces: USB, GigE, and CameraLink. Currently, only CameraLink Bonito cameras using NI IMAQ frame grabber are supported. It has been tested with Bonito CL-400B/C and NI IMAQ frame grabber.

The code is located in `pylablib.devices.AlliedVision`, and the main camera class is `pylablib.devices.AlliedVision.BonitoIMAQCamera`.

## Software requirements

Since the camera control is done purely through the frame grabber interface, the requirements are the same as for generic *IMAQ cameras*. However, the correct camera file still needs to be specified to determine the correct serial communication parameters (especially the termination character)

## Connection

The cameras are identified by their name, which usually looks like "img0". To get the list of all cameras, you can use NI MAX (Measurement and Automation Explorer), or `IMAQ.list_cameras()`:

```
>> from pylablib.devices import IMAQ, AlliedVision
>> IMAQ.list_cameras()
['img0']
>> cam = AlliedVision.BonitoIMAQCamera('img0')
>> cam.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- `Bonito.BonitoIMAQCamera` supports all of `IMAQ.IMAQCamera` features, such as trigger control and fast buffer acquisition. Some methods have been modified to make them more convenient: e.g., `Bonito.BonitoIMAQCamera.set_roi()` method sets the camera ROI and automatically adjusts the frame grabber ROI to match.
- Internally the camera only supports vertical ROI (number of rows), so the horizontal ROI is set via the frame grabber. This means that regardless of the horizontal ROI settings the whole rows are always transmitted between the camera and the frame grabber, so it does not affect, e.g., the maximal frame rate.
- The camera supports a status line, which replaces the first 8 pixels in the upper row encoded frame number. You can use `AlliedVision.Bonito.get_status_lines()` function to identify and extract the data in the status lines from the supplied frames. Note that due to the full row transfer mentioned earlier, the status line is only available if the horizontal ROI span starts from zero; otherwise, it will be partially or completely cut off.
- You can use the function `AlliedVision.Bonito.check_grabber_association()` to check if the given IMAQ camera is a Bonito model by sending several standard Bonito commands and checking replies.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

---

## Basler cameras interface

Basler manufactures a wide variety of cameras, which implement GenICam-based interface through its pylon API. It has been tested with pylon-provided emulated camera.

The code is located in `pylablib.devices.Basler`, and the main camera class is `pylablib.devices.Basler.BaslerPylonCamera`.

## Software requirements

These cameras require PylonC\_vX\_Y.dll (where X and Y is the pylon version, e.g., PylonC\_V7\_1.dll), which is installed with the freely available upon registration [Basler pylon Camera Software Suite](#) (the current latest version is 7.1.0). Note that the DLLs are contained in the pylon SDK, which is only included in the “developer” version of the suite, and not in the “camera user” (default) version. After installation, the path to the DLL (for pylon 7.1.0 located by default in Basler/pylon 7/Runtime/x64 folder in Program Files) is automatically added to system PATH variable, which is one of the places where pylablib looks for it by default. If the DLLs are located elsewhere, the path (either to the DLL file, or to the containing folder) can be specified using the library parameter `devices/dlls/basler_pylon`:

```
import pylablib as pll
pll.par["devices/dlls/basler_pylon"] = "path/to/dlls"
from pylablib.devices import Basler
cam = Basler.BaslerPylonCamera()
```

## Connection

The cameras are identified either by their index among the present cameras (starting from 0), or by their name. To get the list of all cameras, you can use pylon Viewer, or `Basler.list_cameras`:

```
>> from pylablib.devices import Basler
>> Basler.list_cameras()
[TCameraInfo(name='Emulation (0815-0000)', model='Emulation', serial='0815-0000',
↳ devclass='BaslerCamEmu', devversion='', vendor='Basler', friendly_name='Basler_
↳ Emulation (0815-0000)', user_name='', props={'DeviceFactory': 'CamEmu/BaslerCamEmu 7.1.
↳ 0.19126', 'InterfaceID': 'DefaultInterface', 'TLType': 'CamEmu'})]
>> cam = Basler.BaslerPylonCamera() # by default, connect to the first available camera
>> cam.close()
>> cam = Basler.BaslerPylonCamera(name="Emulation (0815-0000)")
>> cam.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI, starting and stopping acquisition, and operating the frame reading loop. The SDK also provides a universal interface for getting and setting various *camera attributes* using their name. You can use `BaslerPylonCamera.get_attribute_value()` and `BaslerPylonCamera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = Basler.BaslerPylonCamera()
>> cam.get_attribute_value("StatusInformation/AcqInProgress") # check if the camera is_
↳ acquiring
```

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```
0
>> cam.set_attribute_value("Width", 512) # set the ROI width to 512px
>> cam.cav["Width"] # get the exposure; could also use cam.get_attribute_value("Width")
512
```

To see all available attributes, you can call `BaslerPylonCamera.get_all_attributes()` to get a dictionary with attribute objects, and `BaslerPylonCamera.get_all_attribute_values()` to get the dictionary of attribute values. The attribute objects provide additional information: attribute kind (integer, enum, string, etc.), range (either numerical range, or selection of values for enum attributes), description string, etc.:

```
>> cam = Basler.BaslerPylonCamera()
>> attr = cam.get_attribute("Width")
>> attr.description
'This value sets the width of the area of interest in pixels.'
>> attr.writable
True
>> (attr.min, attr.max)
(1, 4096)
```

Since these properties vary a lot between different cameras, it is challenging to write a universal class covering a large range of cameras. Hence, currently the universal class only has the basic camera parameter control such as ROI (without binning), acquisition status, and exposure (if present). For many specific cameras you might need to explore the attributes tree (either using the Python class and, e.g., a console, or via pylon Viewer) and operate them directly in your code.

## Known issues

- Currently only the basic unpacked monochrome pixel formats are supported: Mono8, Mono10, Mono12, Mono16, and Mono32. The reason is that even nominally well-defined types (e.g., Mono12Packed) have different formats for different cameras. Currently any unsupported format will raise an error on readout by default. It is still possible to read these out as raw frame data in the form of 1D or 2D numpy 'u1' array by enabling raw frame readout using `BaslerPylonCamera.enable_raw_readout()` method:

```
>> cam = Basler.BaslerPylonCamera()
>> cam.get_detector_size() # 1024px x 1024px frame
(1024, 1024)
>> cam.set_attribute_value("PixelFormat", "BGRA8Packed") # unsupported format
>> cam.snap().shape
...
BaslerError: pixel format BGRA8Packed is not supported
>> cam.enable_raw_readout("frame") # frame data is returned as a flat array
>> cam.snap().shape # 1024 * 1024 * 4 = 4194304 bytes
(1, 4194304)
```

---

**Note:** General camera communication concepts are described on the corresponding [page](#)

---

## BitFlow Axion frame grabbers interface

BitFlow manufactures several kinds of camera interface cards, including CameraLink. Currently, only newer CameraLink Axion family is supported. It has been tested with NI BitFlow Axion 1xB frame grabbers together with Photon-Focus MV-D1024E camera.

The code is located in `pylablib.devices.BitFlow`, and the main camera class is `pylablib.devices.BitFlow.BitFlowCamera`.

## Software requirements

This interface requires two pieces of software, both freely available on the [BitFlow website](#). First, you need [BitFlow SDK 6.5](#), which also includes all the necessary drivers. The free version does not provide any headers and documentation to the DLLs, so you use it you also need to install the manufacturer-provided Python packages, either for [Python 3.6.6](#), or for [Python 3.8.10](#). Note that only these two Python versions are officially supported.

After installation, the DLL locations are automatically added to the PATH environment variable. To facilitate proper package import and DLL loading on Python 3.8, it is recommended to install BitFlow SDK into its default library, or at least leave BitFlow in the folder name.

## Connection

The cameras are identified by their index, starting from 0. To get the list of all cameras, you can use `BitFlow.list_cameras()`:

```
>> from pylablib.devices import BitFlow
>> cam = BitFlow.BitFlowCamera(bitflow_idx=0)
>> cam.close()
```

## Operation

Unlike most camera classes, the frame grabber interface only deals with the frame transfer between the camera and the PC over the CameraLink interface. Therefore, it can not directly control camera parameters such as exposure, frame rate, triggering, ROI, etc. Some similar-looking parameters are still present, but they have a different meaning:

- ROI is defined within the transferred image, whose size itself is determined by the camera ROI. Hence, e.g., if the camera chip is 1024x1024px and its roi is 512x512, then the frame grabber ROI can go only up to 512x512. Any attempts to set it higher result in the frozen acquisition, as the frame grabber expects a larger frame than it receives, and waits forever to get the rest.

## Fast buffer readout and frames merging

At high frame rates (above ~10kFPS) dealing with each frame individually becomes too slow for Python. Hence, there is an option to read out and process frames in larger 'chunks', which are 3D numpy arrays with the first axis enumerating the frame index. This approach leverages the ability to store several frame buffers in the contiguous memory locations (resulting in a single 3D array), and it essentially eliminates the overhead for dealing with multiple frames at high frame rates, as long as the total data rate is manageable (typically below 600Mb/s).

This option can be accessed by calling using `BitFlowCamera.set_frame_format()` method to set frames format to "chunks". In this case, instead of a list of individual frames (which is the standard behavior), the method returns list of chunks of varying size, which contain several consecutive frames.

On top of that, due to unavoidable Python loop required by the BitFlow Python interface, the frame rate is usually limited to about 2-4kFPS. However, there is a way to overcome this by merging  $n$  consecutive frames to a single “super-frame” with  $n$  times larger height. This merging can be specified by `frame_merge` parameter in the `BitFlowCamera.setup_acquisition()` or `BitFlowCamera.start_acquisition()` methods (by default it is 1, meaning no merging). Adjusting the frame grabber ROI and splitting the resulting files is done transparently for the user; the only difference is that frames always arrive in batches, e.g., with `frame_merge=10` and 10FPS rate the frames will arrive once a second in batches of 10. Therefore, it makes sense to adjust the merging to keep the “merged” frame rate high enough for real-time operations but lower than the 2kFPS limit (e.g., around 100FPS).

## Communication with the camera and camera files

The frame grabber needs some basic information about the camera: sensor size, bit depth, data transfer format, timeouts, aux lines mapping, etc. This information is contained in the so-called camera files, which for Axion cameras have `.bfml` extension. These files can be assigned to cameras using SysReg utility located in the Bin64 folder of your BitFlow installation (by default, `C:\BitFlow SDK 6.5\Bin64`).

In addition, due to limitations of the provided Python interfaces, some operations such as changing ROI and bitness can only be done by altering the camera file. Hence, there is an option to create a temporary camera file and alter it to control these parameters. However, it needs the original camera file to serve as a template (this original file is only used as source and not modified). Since there is no possibility to get a path to this file within the Python interface, it should be provided using `camfile` parameter upon creation.

## Known issues

- As mentioned above, ROI is defined within a frame transferred by the camera. Hence, if it includes pixels with positions outside of the transferred frame, the acquisition will time out. For example, suppose the camera sensor is 1024x1024px, and the *camera* ROI is selected to be central 512x512 region. As far as the frame grabber is concerned, now the camera sensor size is 512x512px. Hence, if you try to set the same *frame grabber* ROI (i.e., 512x512 starting at 256,256), it will expect at least 768x768px frame. Since the frame is, actually, 512x512px, the acquisition will time out. The correct solution is to set frame grabber ROI from 0 to 512px on both axes. In general, it is a good idea to always follow this pattern: control ROI only on camera, and always set frame grabber ROI to cover the whole transfer frame.

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**Note:** General camera communication concepts are described on the corresponding [page](#).

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## DCAM cameras interface

DCAM is the interface used in Hamamatsu cameras. It has been tested with Hamamatsu Orca Flash and ImagEM.

The code is located in `pylablib.devices.DCAM`, and the main camera class is `pylablib.devices.DCAM.DCAMCamera`.

## Software requirements

These cameras require `dcamapi.dll`, which is installed with most of Hamamatsu software (such as HoKaWo or HiPic), as well as with the freely available [DCAM API](#), which also includes all the necessary drivers. Keep in mind, that you also need to install the drivers for required corresponding camera type (USB, Ethernet, IEEE 1394). These drivers are in the same installer, but need to be installed separately. You should also pay attention to the cameras supported by the given DCAM driver version, since newer version do not support older cameras (e.g., ImageEM C9100 cameras are only supported up to version 15). After installation, the DLL is automatically added to the System32 folder, where pylablib looks for it by default. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/dcamapi`:

```
import pylablib as pll
pll.par["devices/dlls/dcamapi"] = "path/to/dlls"
from pylablib.devices import DCAM
cam = DCAM.DCAMCamera()
```

## Connection

The cameras are identified by their index, starting from zero. To get the total number of cameras, you can run `DCAM.get_cameras_number()`:

```
>> from pylablib.devices import DCAM
>> DCAM.get_cameras_number()
2
>> cam1 = DCAM.DCAMCamera(idx=0)
>> cam2 = DCAM.DCAMCamera(idx=1)
>> cam1.close()
>> cam2.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. The SDK also provides a universal interface for getting and setting various *camera attributes* (called “properties” in the documentation) using their name. You can use `DCAMCamera.get_attribute_value()` and `DCAMCamera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = DCAM.DCAMCamera()
>> cam.get_attribute_value("BINNING") # get the camera binning (no binning, by default)
1
>> cam.set_attribute_value("EXPOSURE TIME", 0.1) # set the exposure to 100ms
>> cam.cav["EXPOSURE TIME"] # get the exposure; could also use cam.get_attribute_value(
↳ "EXPOSURE TIME")
0.1
```

To see all available attributes, you can call `DCAMCamera.get_all_attributes()` to get a dictionary with attribute objects, and `DCAMCamera.get_all_attribute_values()` to get the dictionary of attribute values, with an option of representing enum attributes either as text or as integer values. The attribute objects provide additional information: attribute range, step, and units:



```
>> cam = DCAM.DCAMCamera()
>> attr = cam.get_attribute("EXPOSURE TIME")
>> (attr.min, attr.max)
(0.001, 10.0)
```

Additionally, there's a couple of differences from the standard libraries worth highlighting:

- The library supports only symmetric binning, i.e., the binning factor is the same in both directions. For compatibility `DCAMCamera.get_roi()` and `DCAMCamera.set_roi()` still return and accept both binning parameters independently, but they are always the same when returned, and `vbin` is ignored when set.
- By default, the SDK does not provide independent control of the frame period and the exposure. Hence, `set_frame_period` method is unavailable, and the frame rate is defined solely by the exposure.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

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## NI IMAQ frame grabbers interface

NI IMAQ is the interface from National Instruments, which is used in a variety of frame grabbers. It has been tested with NI PCI-1430 and PCI-1433 frame grabbers together with PhotonFocus MV-D1024E camera.

The code is located in `pylablib.devices.IMAQ`, and the main camera class is `pylablib.devices.IMAQ.IMAQCamera`.

## Software requirements

This interfaces requires `imaq.dll`, which is installed with the freely available [Vision Acquisition Software](#), which also includes all the necessary drivers. After installation, the DLL is automatically added to the `System32` folder, where `pylablib` looks for it by default. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/niimaq`:

```
import pylablib as pll
pll.par["devices/dlls/niimaq"] = "path/to/dlls"
from pylablib.devices import IMAQ
cam = IMAQ.IMAQCamera()
```

## Connection

The cameras are identified by their name, which usually looks like `"img0"`. To get the list of all cameras, you can use `NI MAX` (Measurement and Automation Explorer), or `IMAQ.list_cameras()`:

```
>> from pylablib.devices import IMAQ
>> IMAQ.list_cameras()
['img0', 'img1']
>> cam1 = IMAQ.IMAQCamera('img0')
>> cam2 = IMAQ.IMAQCamera('img1')
>> cam1.close()
>> cam2.close()
```



## Operation

Unlike most camera classes, the frame grabber interface only deals with the frame transfer between the camera and the PC over the CameraLink interface. Therefore, it can not directly control camera parameters such as exposure, frame rate, triggering, ROI, etc. Some similar-looking parameters are still present, but they have a different meaning:

- External trigger controls frame *transfer*, not frame *acquisition*, which is defined by the camera. By default, when the internal frame grabber trigger is used, the frame grabber transfer rate is synchronized to the camera, so every frame gets transferred. However, if the external transfer trigger is used and it is out of sync with the camera, it can result in duplicate or missing frames.
- ROI is defined within the transferred image, whose size itself is determined by the camera ROI. Hence, e.g., if the camera chip is 1024x1024px and its roi is 512x512, then the frame grabber ROI can go only up to 512x512. Any attempts to set it higher result in the frozen acquisition, as the frame grabber expects a larger frame than it receives, and waits forever to get the rest.

The SDK also provides a universal interface for getting and setting various camera attributes using their name. You can use `IMAQCamera.get_grabber_attribute_value()` and `IMAQCamera.set_grabber_attribute_value()` for that:

```
>> cam = IMAQ.IMAQCamera()
>> cam.get_grabber_attribute_value("FRAMEWAIT_MSEC") # frame read request timeout
1000
```

To get all available attributes as a dictionary, you can call `IMAQCamera.get_all_grabber_attribute_values()`. Their meaning, as well as descriptions of trigger modes and other settings, is explained in the manual supplied with the [Vision Acquisition Software](#).

## Fast buffer readout mode

At high frame rates (above ~10kFPS) dealing with each frame individually becomes too slow for Python. Hence, there is an option to read out and process frames in larger ‘chunks’, which are 3D numpy arrays with the first axis enumerating the frame index. This approach leverages the ability to store several frame buffers in the contiguous memory locations (resulting in a single 3D array), and it essentially eliminates the overhead of dealing with multiple frames at high frame rates, as long as the total data rate is manageable (typically below 600Mb/s).

This option can be accessed by calling using `IMAQCamera.set_frame_format()` method to set frames format to "chunks" (former way of supplying `fastbuff=True` in `IMAQCamera.read_multiple_images()` is now deprecated). In this case, instead of a list of individual frames (which is the standard behavior), the method returns list of chunks about 1Mb in size, which contain several consecutive frames.

## Communication with the camera and camera files

The frame grabber needs some basic information about the camera: sensor size, bit depth, data transfer format, timeouts, aux lines mapping, etc. In NI MAQ this information is contained in the so-called camera files. These files can be assigned to cameras in the NI MAX, and are usually supplied by NI or by the camera manufacturer. In addition, NI MAX allows one to adjust some settings within these files, which are read-only within the NI IMAQ software. These include frame timeout and camera bit depth.

The communication with the camera itself greatly varies between different cameras. Some will have additional connection to control the parameters. Others use serial communication built into the CameraLink interface. This communication can be set up with `IMAQCamera.setup_serial_params()` and used via `IMAQCamera.serial_read()` and `IMAQCamera.serial_write()`. The communication protocols are camera-dependent, and are frequently described in the camera manual. However, some other cameras (e.g., Photon Focus) use proprietary communication protocol. In

this case, they provide their own DLLs, which independently use NI-provided DLLs for serial communication (most notably, `clallserial.dll`) to communicate with the camera. In this case, one needs to maintain two independent connections: one directly to the NI frame grabber to obtain the frame data, and one to the manufacturer library to control the camera. This is the way it is implemented in *PhotonFocus* camera interface.

### Known issues

- Sometimes when the acquisition is stopped and restarted without being cleared, the acquired frame counter does not refresh. This might show up as the software not reporting any new frames. It has been tracked down to a very low (~1ms) frame read timeout. Hence, it is recommended to keep this timeout at least at 500ms.
- If you are unable to access full camera sensor size, check the camera file (it can be opened in the text editor). `MaxImageSize` parameter defines the maximal allowed image size, and it should be equal to the camera sensor size.
- Same goes for bitness. If the camera bitness is higher than set up in the frame grabber, a single camera pixel gets treated as several pixels by the frame grabber, typically resulting in 1px-wide vertical stripes on the image. In the opposite case, the frame grabber expects more bytes than the camera sends, it never receives the full frame, and the acquisition times out.
- Keep in mind that as long as the frame grabber is accessed in NI MAX, it is blocked from use in any other software. Hence, you need to close NI MAX before running your code.
- As mentioned above, ROI is defined within a frame transferred by the camera. Hence, if it includes pixels with positions outside of the transferred frame, the acquisition will time out. For example, suppose the camera sensor is 1024x1024px, and the *camera* ROI is selected to be central 512x512 region. As far as the frame grabber is concerned, now the camera sensor size is 512x512px. Hence, if you try to set the same *frame grabber* ROI (i.e., 512x512 starting at 256,256), it will expect at least 768x768px frame. Since the frame is, actually, 512x512px, the acquisition will time out. The correct solution is to set frame grabber ROI from 0 to 512px on both axes. In general, it is a good idea to always follow this pattern: control ROI only on camera, and always set frame grabber ROI to cover the whole transfer frame.
- Some frame grabbers have a limit on the data transfer rate (for one model observed to be about 200 Mb/s). If the camera data generation rate exceeds it (e.g., it produces 1024x1024px 16-bit frames at >100FPS), then the camera will raise `IMG_ERR_FIFO` error shortly after the acquisition start. In this case, you will need to reduce the data rate by reducing the frame rate or frame size (through ROI, binning, or bitness).

---

**Note:** General camera communication concepts are described on the corresponding [page](#)

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### NI IMAQdx cameras interface

NI IMAQdx is the interface provided by National Instruments and which supports a wide variety of cameras. It is completely separate from IMAQ, and it supports different communication interfaces: USB, Ethernet and FireWire. It has been tested with Ethernet-connected PhotonFocus HD1-D1312 camera.

The code is located in `pylablib.devices.IMAQdx`, and the main camera class is `pylablib.devices.IMAQdx.IMAQdxCamera`.

## Software requirements

These cameras require `imaqdx.dll`, which is installed with the freely available [Vision Acquisition Software](#). However, the IMAQdx part of the software is proprietary, and requires purchase to use. If the software license is invalid, then any attempt to communicate with cameras will result in `License not activated` error (although simply listing the cameras still works). After installation, the DLL is automatically added to the `System32` folder, where `pylablib` looks for it by default. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/niimaqdx`:

```
import pylablib as pll
pll.par["devices/dlls/niimaqdx"] = "path/to/dlls"
from pylablib.devices import IMAQdx
cam = IMAQdx.IMAQdxCamera()
```

## Connection

The cameras are identified by their name, which usually looks like `"cam0"`. To get the list of all cameras, you can use NI MAX (Measurement and Automation Explorer), or `IMAQdx.list_cameras()`:

```
>> from pylablib.devices import IMAQdx
>> IMAQdx.list_cameras()
['cam0', 'cam1']
>> cam1 = IMAQdx.IMAQdxCamera('cam0')
>> cam2 = IMAQdx.IMAQdxCamera('cam1')
>> cam1.close()
>> cam2.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI, starting and stopping acquisition, and operating the frame reading loop. The SDK also provides a universal interface for getting and setting various *camera attributes* using their name. You can use `IMAQdxCamera.get_attribute_value()` and `IMAQdxCamera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = IMAQdx.IMAQdxCamera()
>> cam.get_attribute_value("StatusInformation/AcqInProgress") # check if the camera is_
↳ acquiring
0
>> cam.set_attribute_value("Width", 512) # set the ROI width to 512px
>> cam.cav["Width"] # get the exposure; could also use cam.get_attribute_value("Width")
512
```

To see all available attributes, you can call `IMAQdxCamera.get_all_attributes()` to get a dictionary with attribute objects, and `IMAQdxCamera.get_all_attribute_values()` to get the dictionary of attribute values. The attribute objects provide additional information: attribute kind (integer, enum, string, etc.), range (either numerical range, or selection of values for enum attributes), description string, etc.:

```
>> cam = IMAQdx.IMAQdxCamera()
>> attr = cam.get_attribute("Width")
>> attr.description
'Width of the Image provided by the device (in pixels).'
```

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```
>> attr.writable
True
>> (attr.min, attr.max)
(448, 1312)
```

Since these properties vary a lot between different cameras, it is challenging to write a universal class covering a large range of cameras. Hence, currently the universal class only has the basic camera parameter control such as ROI (without binning) and acquisition status. For many specific cameras you might need to explore the attributes tree (either using the Python class and, e.g., a console, or via NI MAX) and operate them directly in your code.

## Known issues

- It seems like sometimes the camera communication settings might be interfering with its operation. It can show up in an unexpected way, e.g., as an `Attribute value is out of range` error when starting acquisition. If it looks like this might be the case, it is a good idea to open the camera in NI MAX (note that Ethernet cameras are listed under `Network Devices`, not in the general device list) and try to snap a single frame. NI MAX might report some problems with the settings and suggest resolution methods. Once the camera is operational, you can close NI MAX and save the camera settings (request is shown upon closing).
- In general, Ethernet cameras work better with larger packet sizes. However, packets above 1500 bits (so-called jumbo packets) are not supported by all network adapters by default. If this is the case, any attempt to acquire images causes `IMAQdxErrorTestPacketNotReceived` error. One way to deal with that is to set the packet size to 1500, which is done automatically when `small_packet=True` is supplied upon the camera creation. The other is to enable jumbo packets in the adapter properties (in Windows this is done in Device Manager).
- Currently only the basic unpacked monochrome pixel formats are supported: `Mono8`, `Mono10`, `Mono12`, `Mono16`, and `Mono32`. The reason is that even nominally well-defined types (e.g., `Mono12Packed`) have different formats for different cameras. Currently any unsupported format will raise an error on readout by default. It is still possible to read these out as raw frame data in the form of 1D or 2D numpy 'u1' array by enabling raw frame readout using `IMAQdxCamera.enable_raw_readout()` method:

```
>> cam = IMAQdx.IMAQdxCamera()
>> cam.get_detector_size() # 1280px x 1024px frame
(1280, 1024)
>> cam.set_attribute_value("PixelFormat", "BGRA 8 Packed") # unsupported format
>> cam.snap().shape
...
IMAQdxError: pixel format BGRA 8 Packed is not supported
>> cam.enable_raw_readout("frame") # frame data is returned as a flat array
>> cam.snap().shape # 1280 * 1024 * 4 = 5242880 bytes
(5242880,)
```

---

**Note:** General camera communication concepts are described on the corresponding [page](#).

---

## Photon Focus pfcam interface

Photon Focus CameraLink cameras transfer their data to the PC using frame grabbers (e.g., via *NI IMAQ* or *Silicon Software* interfaces). Hence, the camera control is done through the serial port built into the CameraLink interface. However, the cameras use a closed binary protocol, so all the control is done through the pfcam library provided by Photon Focus. It relies on the libraries exposed by the frame grabber manufacturers (e.g., the standard `cl*serial.dll`) to communicate with the camera directly, meaning that the pfcam user simply calls its method, and all the communication happens behind the scenes.

In principle, pfcam can work with any frame grabber. Because of that, there are two different kinds of classes for this camera. To start with, there is `.PhotonFocus.IPhotonFocusCamera`, which provides interface for addressing camera properties, but can not handle actual frame acquisition. Using this class directly leads to errors in any frame data related methods (e.g., `wait_for_frame`, or `read_multiple_images`), and it is mostly intended to serve as a base class to be combined with the actual frame grabber. Two such combined classes are already provided: `.PhotonFocus.PhotonFocusIMAQCamera` for National Instruments frame grabbers using the *NI IMAQ* interface, `.PhotonFocus.PhotonFocusSiSoCamera` for *Silicon Software* frame grabbers, and `.PhotonFocus.PhotonFocusBitFlowCamera` for *BitFlow* frame grabbers. All classes are complete and ready to use. In addition to combining camera and frame grabber control, they also implement basic consistency support, such as automatic adjustment of frame grabber ROI and data transfer format.

## Software requirements

These cameras require `pfcam.dll`, which is installed with freely available (upon registration) `PFInstaller`. In addition, this DLL requires `comdll.dll` and the DLLs referring to a particular camera, e.g., `mv_d1024e_160.dll`. After installation, the path to the DLLs (all located by default in `Photonfocus/PFRemote/bin` folder in `Program Files`) is automatically added to system `PATH` variable, which is one of the places where `pylablib` looks for it by default. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/pfcam`:

```
import pylablib as pll
pll.par["devices/dlls/pfcam"] = "path/to/dlls"
from pylablib.devices import PhotonFocus
cam = PhotonFocus.PhotonFocusIMAQCamera()
```

## Connection

The camera class requires two pieces of information. First is the frame grabber interface connection, e.g., *NI IMAQ* interface name (e.g., `"img0"`) identified as described in the *NI IMAQ* documentation, or *Silicon Software* board and applet described in *Silicon Software* documentation. The second piece of information is the pfcam port, which is either a number starting from zero indexing the port in the ports list, or a tuple (`manufacturer`, `port`), e.g., (`"National Instruments"`, `"port0"`). To list all of the connected pfcam-compatible cameras, you can use the `PFRemote` software (the interface number is given in parentheses after every connection option in the list) or run `PhotonFocus.list_cameras()`:

```
>> from pylablib.devices import PhotonFocus, IMAQ
>> IMAQ.list_cameras() # get all IMAQ frame grabber devices
['img0.iid']
>> PhotonFocus.list_cameras() # by default, get only the ports which support pfcam
↳ interface
[(1, TCameraInfo(manufacturer='National Instruments', port='port0', version=5, type=0))]
>> cam = PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera(imaq_name="img0.iid", pfcam_port=(
↳ "National Instruments", "port0"))
>> cam.close()
```

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```
>> cam = PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera(imaq_name="img0.iid", pfcam_
↳port=1) # same effect as above
>> cam.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- The SDK also provides a universal interface for getting and setting various *camera attributes* (called “properties” in the documentation) using their name. You can use *IPhotonFocusCamera.get\_attribute\_value()* and *IPhotonFocusCamera.set\_attribute\_value()* for that, as well as *.cav* attribute which gives a dictionary-like access:

```
>> cam = PhotonFocus.PhotonFocusIMAQCamera()
>> cam.get_attribute_value("Window/W") # get the ROI width
256
>> cam.set_attribute_value("ExposureTime", 0.1) # set the exposure to 100ms
>> cam.cav["ExposureTime"] # get the exposure; could also use cam.get_attribute_
↳value("ExposureTime")
0.1
```

Some values (e.g., *Window.Max* or *Reset*) serve as commands; these can be invoked using *PhotonFocusIMAQCamera.call\_command()* method. To see all available attributes, you can call *IPhotonFocusCamera.get\_all\_attributes()* to get a dictionary with attribute objects, and *IPhotonFocusCamera.get\_all\_attribute\_values()* to get the dictionary of attribute values. The attribute objects provide additional information: attribute range, step, and units:

```
>> cam = PhotonFocus.PhotonFocusIMAQCamera()
>> attr = cam.get_attribute("Window/W")
>> attr.writable
True
>> (attr.min, attr.max)
(16, 1024)
```

- *PhotonFocus.PhotonFocusIMAQCamera* supports all of *IMAQ.IMAQCamera* features, such as trigger control and fast buffer acquisition. Some methods have been modified to make them more convenient: e.g., *PhotonFocusIMAQCamera.set\_roi()* method sets the camera ROI and automatically adjusts the frame grabber ROI to match.
- Same is true for *PhotonFocus.PhotonFocusSiSoCamera*, which, e.g., provides access to all of the frame grabber variables.
- The camera supports a status line, which replaces the bottom one or two rows of the frame with encoded frame-related data such as frame number and timestamp. You can use *PhotonFocus.get\_status\_lines()* function to identify and extract the data in the status lines from the supplied frames. In addition, you can use *PhotonFocus.remove\_status\_line()* to remove the status lines in several possible ways: zeroing out, masking with the previous frame, cutting off entirely, etc.
- If several *PhotonFocus* cameras are connected, you need to correctly associate different PFCam ports with the corresponding frame grabbers. To do that, you can use the function *PhotonFocus.check\_grabber\_association()*.

---

**Note:** General camera communication concepts are described on the corresponding [page](#)

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## PCO SC2 cameras interface

SC2 is the interface used with PCO cameras. It has been tested with pco.edge cameras with CLHS and regular CameraLink interfaces, and with pco.pixelfly usb cameras. A detailed description of the interface is given in the [manual](#).

The code is located in `pylablib.devices.PCO`, and the main camera class is `pylablib.devices.PCO.PCOSC2Camera`.

## Software requirements

These cameras require SC2\_Cam.dll, which is installed with the freely available [pco.camware](#) and [pco.sdk](#) tools. By default, the library searches for DLLs in Digital Camera Toolbox/Camware4 and PCO Digital Camera Toolbox/pco.sdk/bin folder in Program Files folder (or Program files (x86), if 32-bit version of Python is running), as well as in the folder containing the script. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/pco_sc2`:

```
import pylablib as pll
pll.par["devices/dlls/pco_sc2"] = "path/to/dlls"
from pylablib.devices import PCO
cam = PCO.PCOSC2Camera()
```

## Connection

The cameras are identified by their index, starting from zero, and, possibly, by their interface. To get the total number of connected cameras, you can run `PCO.get_cameras_number`:

```
>> from pylablib.devices import PCO
>> PCO.get_cameras_number()
2
>> cam1 = PCO.PCOSC2Camera(idx=0)
>> cam2 = PCO.PCOSC2Camera(idx=1)
>> cam1.close()
>> cam2.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. The class also provides read-access to all of the relevant camera data using `PCOSC2Camera.get_full_camera_data()`. This method returns data in the internal manufacturer format; to interpret it, you should consult the [manual](#).



## Known issues

- Some cameras support only ROIs which are symmetric with respect to vertical flip. In other words, if the camera detector has vertical size of 2160px, the vertical ROI should always have the form  $(x0, 2160-x0)$ . It is still possible to set non-symmetric ROI, but it is achieved by the software clipping, while the camera still reads out the smallest symmetric ROI contained the selected one. As a result, the readout time for the same ROI size strongly depends on the ROI position. For example, while vertical ROI of  $(0, 8)$  has only 8 pixel rows, it is not symmetric, and requires reading the whole frame; hence, it will be as slow as the full-frame acquisition. On the other hand, ROI of  $(1076, 1084)$  is symmetric, so the camera does read out only 8 rows. This results in vastly faster readout time. You can use `PCOSC2Camera.requires_symmetric_roi()` to check if the symmetric ROI is required.

---

**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Princeton Instruments Picam cameras

Picam is the interface provided by Teledyne Princeton Instruments and which supports a set of their cameras. It has been tested with PIXIS 400 camera.

The code is located in `pylablib.devices.PrincetonInstruments`, and the main camera class is `pylablib.devices.PrincetonInstruments.PicamCamera`.

## Software requirements

These cameras require `picam.dll`, which is installed with the freely available [PICam software](#). By default, the library searches for DLLs in Princeton Instruments/PICam/Runtime folder in Program Files folder (or Program files (x86), if 32-bit version of Python is running), as well as in the folder containing the script. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/picam`:

```
import pylablib as pll
pll.par["devices/dlls/picam"] = "path/to/dlls"
from pylablib.devices import PrincetonInstruments
cam = PrincetonInstruments.PicamCamera()
```

## Connection

The cameras are identified by their serial number, which can look like "2800000001". To get the list of all cameras, you can use `.PrincetonInstruments.list_cameras`:

```
>> from pylablib.devices import PrincetonInstruments
>> PrincetonInstruments.list_cameras()
[TCameraInfo(name='E2V 1340 x 400 (CCD 36)(B)(R)', serial_number='2800000001', model=
↳ 'PIXIS: 400BR', interface='USB 2.0'),
 TCameraInfo(name='E2V 1340 x 400 (CCD 36)(B)(R)', serial_number='2800000002', model=
↳ 'PIXIS: 400BR', interface='USB 2.0')]
>> cam1 = PrincetonInstruments.PicamCamera('2800000001')
>> cam2 = PrincetonInstruments.PicamCamera('2800000002')
>> cam1.close()
>> cam2.close()
```



If no serial number is supplied, the first available camera is connected.

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI, starting and stopping acquisition, and operating the frame reading loop. The SDK also provides a universal interface for getting and setting various *camera attributes* using their name. You can use `PicamCamera.get_attribute_value()` and `PicamCamera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = PrincetonInstruments.PicamCamera()
>> cam.get_attribute_value("Pixel Format") # get the current pixel format
'Monochrome 16-bit'
>> cam.set_attribute_value("Exposure Time", 10) # set the exposure time to 10 ms
>> cam.cav["Exposure Time"] # get the exposure; could also use cam.get_attribute_value(
↪ "Exposure Time")
10.0
```

To see all available attributes, you can call `PicamCamera.get_all_attributes()` to get a dictionary with attribute objects, and `PicamCamera.get_all_attribute_values()` to get the dictionary of attribute values. The attribute objects provide additional information: attribute kind (integer, enum, float, etc.), range (either numerical range, or selection of values for enum attributes), default value, etc.:

```
>> cam = PrincetonInstruments.PicamCamera()
>> attr = cam.get_attribute("Exposure Time")
>> attr.default
100.0
>> attr.writable
True
>> (attr.min, attr.max)
(0.0, 8355840.0)
```

Since these properties vary a lot between different cameras, it is challenging to write a universal class covering a large range of cameras. Hence, currently the universal class only has the basic camera parameter control such as ROI (without binning), exposure, and acquisition status. For many specific cameras you might need to explore the attributes tree using the Python class and operate them directly in your code.

## Known issues

- Frame period obtained using `PicamCamera.get_frame_period()` can be an underestimate (i.e., it can overestimate the frame rate).
- While the cameras support multiple ROIs, only single-ROI readout is currently supported.
- Changing readout mode ("Readout Control Mode") to "Kinetics" might invalidate the current ROI, if it was originally too large. Therefore, you would need to call `set_roi` again after setting this mode.
- In principle, the cameras support a variety of different metainfos which can be enabled or disabled separately. However, for simplicity only two modes are supported in the camera class: either no metainfo, or full "standard" metainfo (frame stamp, and start and stop timestamps). Any time the metainfo is enabled, disabled, or queried, it is automatically "truncated" to one of these two modes.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Photometrics PVCAM cameras

PVCAM is the interface provided by Teledyne Photometrics and which supports a set of their cameras. It has been tested with Prime 95B camera.

The code is located in `pylablib.devices.Photometrics`, and the main camera class is `pylablib.devices.Photometrics.PvcamCamera`.

## Software requirements

These cameras require `pvcam32.dll` or `pvcam64.dll`, which is installed with the freely available (upon registration) [PVCAM software](#). By default, the library searches for DLL is automatically added to the `System32` folder, where `pylablib` looks for them by default. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/pvcam`:

```
import pylablib as pll
pll.par["devices/dlls/pvcam"] = "path/to/dlls"
from pylablib.devices import Photometrics
cam = Photometrics.PvcamCamera()
```

## Connection

The cameras are identified by their name, which can look like `"PMUSBCam00"`. To get the list of all cameras, you can use `.Photometrics.list_cameras`:

```
>> from pylablib.devices import Photometrics
>> Photometrics.list_cameras()
['PMUSBCam00', 'PMUSBCam01']
>> cam1 = Photometrics.PvcamCamera('PMUSBCam00')
>> cam2 = Photometrics.PvcamCamera('PMUSBCam01')
>> cam1.close()
>> cam2.close()
```

If no name is supplied, the first camera in the list is connected.

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI, starting and stopping acquisition, and operating the frame reading loop. The SDK also provides a universal interface for getting and setting various *camera attributes* using their name. You can use `PvcamCamera.get_attribute_value()` and `PvcamCamera.set_attribute_value()` for that, as well as `.cav` attribute which gives a dictionary-like access:

```
>> cam = Photometrics.PvcamCamera()
>> cam.get_attribute_value("EXPOSURE_MODE") # get the current exposure mode
'Internal Trigger'
>> cam.set_attribute_value("METADATA_ENABLED", True) # enable frame metadata
>> cam.cav["METADATA_ENABLED"] # check if metadata is enabled; could also use cam.get_
↪ attribute_value("METADATA_ENABLED")
True
```

To see all available attributes, you can call `PvcamCamera.get_all_attributes()` to get a dictionary with attribute objects, and `PvcamCamera.get_all_attribute_values()` to get the dictionary of attribute values. The attribute

objects provide additional information: attribute kind (integer, enum, float, etc.), range (either numerical range, or selection of values for enum attributes), default value, etc.:

```
>> cam = Photometrics.PvcamCamera()
>> attr = cam.get_attribute("EXPOSURE_TIME")
>> attr.default
0
>> attr.readable
True
>> (attr.min, attr.max)
(0, 100000)
```

Since these properties vary a lot between different cameras, it is challenging to write a universal class covering a large range of cameras. Hence, currently the universal class only has the basic camera parameter control such as ROI (without binning), exposure, and acquisition status. For many specific cameras you might need to explore the attributes tree using the Python class and operate them directly in your code.

### Fast buffer readout mode

At high frame rates (above ~10kFPS) dealing with each frame individually becomes too slow for Python. Hence, there is an option to read out and process frames in larger 'chunks', which are 3D numpy arrays with the first axis enumerating the frame index. This approach leverages the ability to store several frame buffers in the contiguous memory locations (resulting in a single 3D array), and it essentially eliminates the overhead for dealing with multiple frames at high frame rates, as long as the total data rate is manageable (typically below 600Mb/s).

This option can be accessed by calling using `PvcamCamera.set_frame_format()` method to set frames format to "chunks". In this case, instead of a list of individual frames (which is the standard behavior), the method returns list of chunks, which contain several consecutive frames.

### Known issues

- Frame period obtained using `PvcamCamera.get_frame_period()` can be an underestimate (i.e., it can overestimate the frame rate), especially for USB-connected devices.
- While the cameras support multiple ROIs, only single-ROI readout is currently supported.
- Exposure time, exposure mode, and ROI are configured using special methods separately from other camera attributes. Therefore, their corresponding attributes are read-only.
- Not all horizontal and vertical binning combinations are supported. The allowed combinations can be queried using `PvcamCamera.get_supported_binning_modes()`. If the combination is not supported, it is truncated down to the smallest supported one.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Silicon Software frame grabbers interface

Silicon Software produces a range of frame grabbers, which can be used to control different cameras with a CameraLink interface. It has been tested with microEnable IV AD4-CL frame grabber together with PhotonFocus MV-D1024E camera.

The code is located in `pylablib.devices.SiliconSoftware`, and the main camera class is `pylablib.devices.SiliconSoftware.SiliconSoftwareCamera`.

## Software requirements

This interfaces requires `fglib5.dll`, which is installed with the freely available (upon registration) [Silicon Software Runtime Environment](#) (the newest version for 64-bit Windows is 5.7.0), which also includes all the necessary drivers. After installation, the path to the DLL (located by default in `SiliconSoftware/Runtime5.7.0/bin` folder in Program Files) is automatically added to system PATH variable, which is one of the places where `pylablib` looks for it by default. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/sisofgrab`:

```
import pylablib as pll
pll.par["devices/dlls/sisofgrab"] = "path/to/dlls"
from pylablib.devices import SiliconSoftware
cam = SiliconSoftware.SiliconSoftwareCamera()
```

## Connection

Figuring out the connection parameters is a multi-stage process. First, one must identify one of several boards. The boards can be identified using `SiliconSoftware.list_boards` function. Second, one must select an applet. These provide different board readout modes and, for Advanced Applets, various post-processing capabilities. These applets can be identified using `SiliconSoftware.list_applets` method, or directly from the Silicon Software RT microDisplay software supplied with the runtime. The choice depends on the color mode (color vs. gray-scale and different bitness), readout mode (area or line), and camera connection (single, double, or quad). Finally, depending on the board and the camera connection, one of several ports must be selected. For example, if the frame grabber has two connectors, but the camera only uses a single interface, then the double camera applet (e.g., `DualAreaGray16`) must be selected, and the port should specify the board connector (0 for A, 1 for B):

```
>> from pylablib.devices import SiliconSoftware
>> SiliconSoftware.list_boards() # first list the connected boards
[BoardInfo(name='mE4AD4-CL', full_name='microEnable IV AD4-CL')]
>> SiliconSoftware.list_applets(0) # list all applets on the first board
[ ...,
  TAppletInfo(name='DualAreaGray16', file='DualAreaGray16.dll'),
  ... ]
>> cam = SiliconSoftware.SiliconSoftwareCamera(0, 'DualAreaGray16') # connect to the
↳ first board (port 0 by default)
>> cam.close()
```

Note that currently the code is organized in such a way, that only one port on a single board can be in use at one time.

## Operation

Unlike most camera classes, the frame grabber interface only deals with the frame transfer between the camera and the PC over the CameraLink interface. Therefore, it can not directly control camera parameters such as exposure, frame rate, triggering, ROI, etc. Some similar-looking parameters are still present, but they have a different meaning:

- External trigger controls frame *transfer*, not frame *acquisition*, which is defined by the camera. By default, when the internal frame grabber trigger is used, the frame grabber transfer rate is synchronized to the camera, so every frame gets transferred. However, if the external transfer trigger is used and it is out of sync with the camera, it can result in duplicate or missing frames.
- ROI is defined within the transferred image, whose size itself is determined by the camera ROI. Hence, e.g., if the camera chip is 1024x1024px and its roi is 512x512, then the frame grabber ROI can go only up to 512x512. Any attempts to set it higher result in frame being misshapen or having random data outside of the image area.

The SDK also provides a universal interface for getting and setting various *attributes* using their name. You can use `SiliconSoftwareCamera.get_grabber_attribute_value()` and `SiliconSoftwareCamera.set_grabber_attribute_value()` for that, as well as `.gav` attribute which gives a dictionary-like access:

```
>> cam = SiliconSoftware.SiliconSoftwareCamera()
>> cam.get_grabber_attribute_value("CAMERA_LINK_CANTYP") # get the camera data format
'FG_CL_SINGLETAP_8_BIT'
>> cam.set_grabber_attribute_value("WIDTH", 512) # set the readout frame width to 512px
>> cam.gav["WIDTH"] # get the width; could also use cam.get_grabber_attribute_value(
    ↪ "WIDTH")
512
```

To see all available attributes, you can call `SiliconSoftwareCamera.get_all_grabber_attributes()` to get a dictionary with attribute objects, and `SiliconSoftwareCamera.get_all_grabber_attribute_values()` to get the dictionary of attribute values. The attribute objects provide additional information: attribute kind (integer, string, etc.), range (either numerical range, or selection of values for enum attributes), description string, etc.:

```
>> cam = SiliconSoftware.SiliconSoftwareCamera()
>> attr = cam.get_grabber_attribute("BITALIGNMENT")
>> attr.values
{1: 'FG_LEFT_ALIGNED', 0: 'FG_RIGHT_ALIGNED'}
```

The parameter can also be inspected in the Silicon Software RT microDisplay software.

## Fast buffer readout mode

At high frame rates (above ~10kFPS) dealing with each frame individually becomes too slow for Python. Hence, there is an option to read out and process frames in larger ‘chunks’, which are 3D numpy arrays with the first axis enumerating the frame index. This approach leverages the ability to store several frame buffers in the contiguous memory locations (resulting in a single 3D array), and it essentially eliminates the overhead for dealing with multiple frames at high frame rates, as long as the total data rate is manageable (typically below 600Mb/s).

This option can be accessed by calling using `SiliconSoftwareCamera.set_frame_format()` method to set frames format to "chunks" (former way of supplying `fastbuff=True` in `SiliconSoftwareCamera.read_multiple_images()` is now deprecated). In this case, instead of a list of individual frames (which is the standard behavior), the method returns list of chunks about 1Mb in size, which contain several consecutive frames.

## Communication with the camera

The frame grabber needs some basic information about the camera: sensor size, bit depth, data transfer format, timeouts, aux lines mapping. This information can be specified using the grabber attributes. The most important transfer parameters are the number of taps and the bitness of the transferred data, which can be set up using `SiliconSoftwareCamera.setup_camlink_pixel_format()`. The values for this parameters can usually be obtained from the camera manuals.

## Known issues

- The maximal frame rate is limited for some boards (at least for the tested microEnable IV AD4-CL board) by about 20kFPS. It seems to be relatively independent of the frame size, i.e., it is not the data transfer rate issue. One possible way to get around it is to use line readout applet, e.g., `DualLineGray16`, and set the frame height to be the integer multiple of the camera frame. This will combine several camera frames into a single frame-grabber frame, effectively lowering the frame rate at avoiding the issue. However, this sometimes leads to incorrect frame splitting: the top line of the “combined” frame does not coincide with the top line of the original camera frame, so all frames are shifted cyclically by some number of rows. Hence, it might require some post-processing with frames merging and re-splitting.
- As mentioned above, ROI is defined within a frame transferred by the camera. Therefore, if it includes pixels with positions outside of the transferred frame, the acquisition will be faulty. For example, suppose the camera sensor is 1024x1024px, and the *camera* ROI is selected to be central 512x512 region. As far as the frame grabber is concerned, now the camera sensor size is 512x512px. Hence, if you try to set the same *frame grabber* ROI (i.e., 512x512 starting at 256,256), it will expect 768x768px frame. Since the frame is, actually, 512x512px, the returned frame will partially contain random data. The correct solution is to set frame grabber ROI from 0 to 512px on both axes. In general, it is a good idea to always follow this pattern: control ROI only on camera, and always set frame grabber ROI to cover the whole transfer frame.

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**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Thorlabs Scientific Cameras interface

This is the interface used in Thorlabs scientific sCMOS cameras such as Kiralux or Zelux. It has been tested with Thorlabs Kiralux camera.

The code is located in `pylablib.devices.Thorlabs`, and the main camera class is `pylablib.devices.Thorlabs.ThorlabsTLCamera`.

## Software requirements

These cameras require `thorlabs_tsi_camera_sdk.dll`, as well as several additional DLLs: `thorlabs_unified_sdk_kernel.dll`, `thorlabs_unified_sdk_main.dll`, `thorlabs_tsi_usb_driver.dll`, `thorlabs_tsi_usb_hotplug_monitor.dll`, `thorlabs_tsi_cs_camera_device.dll`, `tsi_sdk.dll`, `tsi_usb.dll`. All of them is automatically installed with the freely available [ThorCam](#) tools. By default, the library searches for DLLs in Thorlabs/Scientific Imaging/ThorCam folder in Program Files folder (or Program files (x86), if 32-bit version of Python is running), as well as in the folder containing the script. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/thorlabs_tlcam`:

```
import pylablib as pll
pll.par["devices/dlls/thorlabs_tlcam"] = "path/to/dlls"
```

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```
from pylablib.devices import Thorlabs
cam = Thorlabs.ThorlabsTLCamera()
```

## Connection

The cameras are identified by their serial number. To list all of the connected cameras, you can run `Thorlabs.list_cameras_tlcam()`:

```
>> from pylablib.devices import Thorlabs
>> Thorlabs.list_cameras_tlcam()
['12001', '12002']
>> cam1 = Thorlabs.ThorlabsTLCamera(serial="12001")
>> cam2 = Thorlabs.ThorlabsTLCamera(serial="12002")
>> cam1.close()
>> cam2.close()
```

If no serial is provided, the software connects to the first available camera.

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop.

For color cameras, several readout modes are available, which can be set up using `ThorlabsTLCamera.set_color_format()` method. By default, the color cameras output the frames in the linear RGB format (each frame is a 3D array with the last axis encoding color channel).

**Warning:** The library appears to be not entirely stable: every time acquisition start is issued, there is small (0.1-1%) chance that it will not actually start, which results in timeout errors. Furthermore, there are occasional crashes on the SDK unloading (i.e., camera closing), especially when acquisition has been started and stopped multiple times. It is unclear, what is the cause of this behavior, but it seems to originate from the manufacturer's DLL (bare-bones example and the native Python library reproduce this behavior). Hence, it might be different with different DLL versions.

**Note:** The DLL prints some debug information in the console when camera list is requested and when the camera is opened. At the moment, it is unclear how to get rid of it.

**Note:** General camera communication concepts are described on the corresponding [page](#)



## Uc480/uEye camera interface

This is the interface used in multiple cameras, including many simple Thorlabs and IDS cameras. It has been tested with IDS SC2592R12M and Thorlabs DCC1545M.

Essentially identical interface is available under two different implementations: either as Thorlabs uc480 or as IDS uEye. Both of these seem to cover exactly the same cameras, both are freely available from the manufacturers, and both implement exactly the same functionality. However, these interfaces are not interchangeable, and each camera will only interact with one of them depending on which driver it happens to use (usually based on which of the software packages was installed last). Hence, if you have both [ThorCam](#) and [IDS Software Suite](#) installed, you would need to check both interfaces. Normally, the interface should correspond to the software which can connect to the camera (either ThorCam or uEye Cockpit).

The code is located in `pylablib.devices.uc480`, and the main camera class is `pylablib.devices.uc480.UC480Camera`. Note that while the names only refer to uc480, the same functions and classes equally cover IDS uEye interface if the appropriate backend argument is provided.

## Software requirements

Depending on the interface, these cameras require either `uc480.dll`, or `ueye_api.dll`. These are automatically installed with, correspondingly, the freely available [ThorCam](#) software or with [IDS Software Suite](#) (upon registration; note that you need specifically IDS Software Suite, and not IDS peak). By default, the library searches for DLLs in the corresponding Program Files folder (Thorlabs/Scientific Imaging/ThorCam or IDS/uEye), in the locations placed in PATH during the installation, as well as in the folder containing the script. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/uc480` or `devices/dlls/ueye`:

```
import pylablib as pll
pll.par["devices/dlls/uc480"] = "path/to/uc480/dlls"
from pylablib.devices import uc480
cam = uc480.UC480Camera()
pll.par["devices/dlls/ueye"] = "path/to/ueye/dlls"
cam = uc480.UC480Camera(backend="ueye")
```

## Connection

The cameras are identified by their camera ID or device ID (both starting from 1). Device ID corresponds to the connection order of the cameras: it is guaranteed to be unique, but will change if the camera is disconnected and reconnected again. On the other hand, camera ID is tied to the camera, but it is set to 1 by default for all cameras, and needs to be manually assigned using `UC480Camera.set_camera_id()`. Alternatively, one can use other characteristics (model or serial number) as a unique identifier. To list all of the connected cameras together with their basic information, you can run `uc480.list_cameras()`:

```
>> from pylablib.devices import uc480
>> uc480.list_cameras()
[TCameraInfo(cam_id=4, dev_id=1, sens_id=11, model='SC2592R12M', serial_number=
  ↳ '1234567890', in_use=False, status=0)]
>> cam = uc480.UC480Camera(cam_id=4) # connect to the camera using cam_id
>> img = cam.snap()
>> cam.close()
>> cam = uc480.UC480Camera(dev_id=1) # connecting to the same camera using dev_id
>> cam.close()
```

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```
>> cam = uc480.UC480Camera() # connecting to the first available camera
>> cam.close()
```

If `cam_id = 0` is provided (default), the software connects to the first available camera.

By default, the code above uses Thorlabs uc480 interface. If you want to use ueye interface, you need to specify `backend="ueye"` argument to the corresponding functions and to the camera class upon creation. With that, the example above becomes:

```
>> from pylablib.devices import uc480
>> uc480.list_cameras(backend="ueye") # list all cameras for uEye backend
[TCameraInfo(cam_id=4, dev_id=1, sens_id=11, model='SC2592R12M', serial_number=
→ '1234567890', in_use=False, status=0)]
>> cam = uc480.UC480Camera(cam_id=4, backend="ueye") # connect to the camera using cam_
→ id and ueye backend
>> img = cam.snap()
>> cam.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI and exposure, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- Some cameras support both binning (adding several pixels together) and subsampling (skipping some pixels). However, only one can be enabled at a time. They can be set independently using, correspondingly, `UC480Camera.get_binning()/UC480Camera.set_binning()` and `UC480Camera.get_subsampling()/UC480Camera.set_subsampling()`. They can also be set as binning factors in `UC480Camera.get_roi()/UC480Camera.set_roi()`. Whether binning or subsampling is set there can be determined by the `roi_binning_mode` parameter supplied on creation.
- Uc480 API supports many different pixel modes, including packed ones. However, pylablib currently supports only monochrome unpacked modes.
- Occasionally (especially at high frame rates) frames get skipped during transfer, before they are placed into the frame buffer by the camera driver. This can happen in two different ways. First, the frame is simply dropped without any indication. This typically can not be detected without using the frame stamp contained in the frame info, as the frames flow appear to be uninterrupted. In the second way, the acquisition appears to get “restarted” (the internal number of acquired frames is dropped to zero), which is detected by the library. In this case there are several different ways the software can react, which are controlled using `UC480Camera.set_frameskip_behavior()`.

The default way to address this “restart” event (“ignore”) is to ignore it and only adjust the internal acquired frame counter; this manifests as quietly dropped frames, exactly the same as the first kind of event. In the other method (“skip”), some number of frames are marked as skipped, so that the difference between the number of acquired frames and the internal frame stamp is kept constant. This makes the gap explicit in the camera frame counters. Finally (“error”), the software can raise `uc480.FrameTransferError` when such event is detected, which can be used to, e.g., restart the acquisition.

One needs to keep in mind, that while the last two methods make “restarts” more explicit, they do not address the first kind of events (quiet drops). The most direct way to deal with them is to use frame information by setting `return_info=True` in frame reading methods like `read_multiple_images`. This information contains the internal camera frame stamp, which lets one detect any skipped frames.

---

**Note:** General camera communication concepts are described on the corresponding [page](#)

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## Mightex cameras interface

Mightex manufactures a set of USB2 and USB3-interfaced cameras with several somewhat different APIs. Currently only S-series cameras are implemented and tested.

The code is located in `pylablib.devices.Mightex`, and the main camera class is `pylablib.devices.Mightex.MightexSSeriesCamera`.

## Software requirements

These cameras require `MT_USBCamera_SDK_DS.dll` and accompanying `MtUsbLib.dll`, which can be obtained in the freely available [S-series camera software package](#) (the current latest version is from 2019.01.04). This software does not require installation, and the required DLLs are contained in the `DirectShow/MightexClassicCameraEngine` folder withing the archive (do not confuse them with the regular `MT_USBCamera_SDK.dll` library, which is similar, but has some downsides regarding threading). Since these DLLs are not registered anywhere OS-wide, you should either specify them using the library parameter `devices/dlls/mightex_sseries` (both the containing folder path and the direct file path work), or copy the two DLL files to the folder containing your script:

```
import pylablib as pll
pll.par["devices/dlls/mightex_sseries"] = "path/to/dlls"
from pylablib.devices import Mightex
cam = Mightex.MightexSSeriesCamera()
```

## Connection

The cameras are identified by their index among the present cameras (starting from 1). To get the list of all cameras, you can use `Mightex.list_cameras_s`:

```
>> import pylablib as pll
>> pll.par["devices/dlls/mightex_sseries"] = "path/to/dlls"
>> from pylablib.devices import Mightex
>> Mightex.list_cameras_s()
[TCameraInfo(idx=1, model='SCE-B013-U', serial='13-160000-001')]
>> cam = Mightex.MightexSSeriesCamera() # by default, connect to the camera with index 1
>> cam.close()
```

## Operation

The operation of these cameras is relatively standard. They support all the standard methods for dealing with ROI, starting and stopping acquisition, and operating the frame reading loop. However, there's a couple of differences from the standard libraries worth highlighting:

- The multi-camera support from the SDK is fairly poor, e.g., only a single OS process can communicate with cameras (even if different processes try to access different cameras), and several cameras are always polled in sequence, meaning that the slowest camera determines the overall frame rate. Therefore, only the single camera operation is supported, although one can still select specific camera if several are connected to the same PC.

- In some cases ROIs with extreme aspect ratios (e.g., 32x1024 px) can freeze the camera, such that it only start operating again after the software restart. Therefore, there should be generally be avoided.
- Colored cameras are in principle supported, but the returned image is not debayered, meaning that it is still a monochrome image with different pixels within 2x2 sub-squares corresponding to different colors.

## 2.2.3 Stages

Basic concepts are described at the [stages communication page](#).

Currently supported stages:

- *Attocube ANC300* and *Attocube ANC350*: most common Attocube positioner controllers. Tested with Ethernet and USB connection for ANC300, and USB connection for ANC350.
- *Thorlabs APT/Kinesis*: basic Thorlabs motorized stages and optomechanics devices. Tested with KDC101, K10CR1, and BSC201 motor controllers, KIM101 piezo motor controller, KPZ101 piezo controllers, as well as MFF101 and FW102 (described at a [different page](#))
- *Thorlabs Elliptec*: resonant piezoelectric Thorlabs stages. Tested with ELL18 and ELL14 rotational mounts.
- *Newport Picomotor*: precision piezo-actuated screws based on slip-stick principle. Tested with Newport 8742 Picomotor driver using Ethernet or USB connection.
- *Arcus Performax*: fairly common single- and multi-axis motor controllers sold under different brands: Arcus, Nippon Pulse America, or Newmark Systems. Tested with PMX-4EX device with USB connection.
- *Trinamic*: universal motor controllers and drivers. Tested with a single-axis TMC2101 controller with USB connection.
- *Standa*: Standa motorized positioners. Tested with a 8SMC4-USB single-axis controller and 8MT167-25 stepper motor stage.
- *SmarAct*: high-performance piezo sliders. Currently simple open-loop *SCU controllers* and *MCS2 controllers* are supported. Tested with a standard HCU controller unit and an MCS2 controller with several SLx stages.
- *Physik Instrumente*: piezo controllers. So far only PI E-515 and PI E-516 is supported and tested.

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**Note:** General device communication concepts are described on the corresponding [page](#).

---

## Stages control basics

### Basic example

Almost all stages implement the same basic functionality for moving, stopping, homing, and querying the status:

```
stage = Thorlabs.KinesisMotor("27000001") # connect to the stage
stage.home() # home the stage
stage.wait_for_home() # wait until homing is done
stage.move_by(1000) # move by 1000 steps
stage.wait_move() # wait until moving is done
stage.jog("+") # initiate jog (continuous move) in the positive direction
time.sleep(1.) # wait for 1 second
stage.stop() # stop the motion
stage.close()
```

Some stages will miss some of these functions (e.g., no homing), but if it's present, it works roughly in the same manner. Some concepts are explained below in more detail.

## **Basic concepts**

### **Counters, encoders, homing, and limit switches**

Stages have two basic strategies for keeping track of the position. The first one is counting the steps. The problem with it is that once the device is powered up, its position is unknown. Hence, it requires some kind of homing procedure, which usually involves moving to a predefined position and zeroing out the step counter there. This position is defined by the hardware, usually in the form of a limit switch: a physical switch located at the end of the stage travel range, which changes the state when the stage reaches its position. It also usually automatically turns off the motion when tripped, to prevent the motor from overheating or the stage from breaking.

When stepper motors are used, the size of each step (or microstep, if used) is a reasonably well-defined fraction of a turn, so counting them gives fairly reproducible results. On the other hand, piezo slip-stick sliders (such as Attocube, SmartAct, or Picomotor) have inherently unreliable steps size which depends on, e.g., load, direction, position, temperature, or other environmental factors. In this case steps counting, while possible, usually leads to long-term drifts.

If the reliable counting is impossible, like in the case of sliders or regular DC (as opposed to stepper) motors, the manufacturer might add a hardware position readout. It can be digital (encoder) or analog (e.g., resistive, capacitive, or optical readout). The first kind is generally simpler, cheaper and more reliable, but the second one can provide much higher resolution, and can work in more extreme environments (high vacuum, cryogenics). In both cases, the controllers would typically have some kind of feedback loop to smoothly control the motion speed and direction to approach a given position.

### **Steps and real coordinates**

Almost all stages allow control or readout of position in motor steps, encoder steps, or some other internal units. It is usually not straightforward, or sometimes even impossible, to convert those to real units. In cases where it is possible, it is defined by the motor gearbox and the screw pitch (for linear stages); in most cases, this ratio is provided in the motor or translation stage manual (which can be different from the motor controller manual, and the two might even be completely independent). Sometimes, one even has to do explicit calculations, e.g., getting the number of microsteps per revolution from the controller and motor manufacturer, and the displacement per step from the stage manufacturer.

### **Speed control**

In many cases, the motor speed is ramped up and down linearly rather than abruptly; hence, both the “cruising” speed and the ramping acceleration can, in principle, be configured. Usually they are defined in, respectively, steps/s and steps/s<sup>2</sup>, although sometimes internal units have to be used.

## Application notes and examples

Here we talk more practically about using pylablib to perform common tasks.

### Motion

The most standard motion methods are `move_to`, which moves to a specified position, `move_by`, which moves by a specified distance or number of steps, and `jog`, which moves continuously in a given direction until stopped or run into a limit switch. If both `move_to` and `move_by` are present, they usually perform the same operation under the hood: `stage.move_by(s)` and `stage.move_to(stage.get_position()+s)` yield the same result.

In almost all cases these commands are asynchronous, in the sense that they simply initialize the motion and continue immediately:

```
>> stage.move_by(1000)
>> stage.is_moving() # the stage is moving, but the execution continues
True
>> time.sleep(1.)
>> stage.is_moving() # after 1s the motion is done
False
```

To stop immediately (which is usually only used with `jog` commands) you can use the `stop` method. In some cases, there are two different stop kinds: “soft” with a ramp-down, or “hard” which immediately ceases motion.

### Status and synchronization

Since the motion commands are asynchronous, the devices provide two methods to synchronize it with the script execution. The first one, `is_moving`, checks if the stage is currently in motion. The second one, `wait_move`, pauses the execution until the stage motion is finished.

In addition, many stages provide methods to obtain additional information, e.g., `get_status` (which, usually, returns state of motion, limit switches, possible errors, etc.), or `get_current_speed`.

### Position readout

If a stage has position readout (either hardware sensor, or step counting), it is implemented with the `get_position` method. In most cases, it will be accompanied with the `set_position_reference` method, which lets one change the currently stored position, effectively adding an offset to all further position readings:

```
>> stage.get_position()
10000
>> stage.set_position_reference(20000) # change current reference to
>> stage.get_position() # note that it reacts immediately, unlike move_to; no physical_
↪motion happened
20000
>> stage.move_to(21000) # move by 1000 steps; equivalent to .move_by(1000), or .move_
↪to(11000) before the reference change
```

Note that it only changes the internal counter state, and does not cause any stage motion (which is performed by `move_to`).

## Axis selection

Many controllers support simultaneous control of several different motors. In this case, all of their methods take an additional `axis` (in most cases) or `channel` argument, which specify the exact motor. In cases where usually only one motor is controlled (e.g., TCM1110 or Thorlabs KDC101), this parameter is set to the default value, and is closer to the end of the parameter list. If having multiple controlled stages is the default (e.g., Attocube ANC350 or Arcus Performax), this parameter is usually the first one, and it has to be specified. In these cases, the methods frequently allow to set this parameter to "all", which means that the action is performed for all axes, or the results are returned for all axes (usually in a form of a list or a dictionary).

The channels are usually specified by their index starting from 0 or 1, although some stages adopt a different labeling (e.g., Arcus Performax labels them as X, Y, Z, and U). The exact specification is given in the specific class description.

## Homing

As mentioned above, often stages require homing to get absolute position readings. It needs to be done every time the stage is power-cycled, but the homing parameters usually persist between different re-connections.

If homing is implemented, it is done using the `home` method. In addition, there can also be an `is_homed` method, which checks if the homing has already been performed. If the method is present, then by default `home` will not execute if `is_homed` returns `True`, unless forced.

Some stages do not have an explicit homing method, but can be manually homed by, e.g., running the stage to the limit switch and setting the position reference to 0.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

---

## Attocube positioners

Attocube has two main positioner controllers: ANC300 and ANC350. These cover different but somewhat overlapping positioner classes, and have fairly different programming interfaces.

### Attocube ANC300

This controller is aimed at open-loop (i.e., no position readout) positioners. It is a chassis with a single PC communication module and up to 7 individual piezo control modules: ANM150 (only stepping), ANM200 (only scanning), or ANM250 (stepping and scanning).

The device class is `pylablib.devices.Attocube.ANC300`.

## Software requirements

The controller has several communication modes: USB, RS232, and Ethernet. USB mode requires a driver supplied with the controller (or downloaded from the controller itself using its Ethernet connection and HTTP port), which makes ANC300 appear as a virtual COM port. RS232 requires a USB-to-RS232 adapter, which usually manifests in the same way. Finally, Ethernet connection works like any other network device. The controller has been tested with USB and Ethernet communication modes (RS232 is identical to USB, so it should operate as well).

Of all of these modes only USB requires specialized drivers, and the other two are usually available purely through the built-in OS capabilities.

## Connection

The device is identified by its communication address. It can be either a serial port (e.g., "COM5"), or an IP address (e.g., "192.168.1.100"); see [connection description](#) for more information. The backend is chosen automatically based on the connection parameter. Additionally, Ethernet connection requires a password; by default, the standard Attocube password "123456" is used, but if you specified a custom password, you need to provide it upon connection:

```
>> from pylablib.devices import Attocube
>> atc1 = Attocube.ANC300("COM5") # USB or RS232 connection
>> atc2 = Attocube.ANC300("192.168.1.1", pwd="root") # Ethernet connection; no need to
↪ provide a password, if it is default
>> atc1.close()
>> atc2.close()
```

Note that since Ethernet inherently supports multiple connections, it is possible to control the same devices in multiple scripts at the same time.

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The controller is inherently multi-axis, hence it always take the axis as the first argument. The axes are numbered starting from 1, and are addressed according to the chassis spaces, so some can be skipped or missing. To update the list of connected axes, use `ANC300.update_available_axes()` (called automatically on connection).
- Different control modules provide different functionality. Hence, not all methods would work for all axes: offset voltage commands such as `ANC300.set_offset()` do not work with ANM150 module, while stepping commands such as `ANC300.move_by()` do not work with ANM200 module. To get the module kinds and serial numbers, use `ANC300.get_axis_serial()`.
- The most important stepping parameters are step voltage amplitude and step frequency (number of steps per second). These can be controlled with, correspondingly, `ANC300.get_voltage()/ANC300.set_voltage()` and `ANC300.get_frequency()/ANC300.set_frequency()`.
- Different axes can be enabled and disabled (i.e., connected or grounded) using `ANC300.enable_axis()` and `ANC300.disable_axis()`. Disabling an axis completely shuts off the connection to the positioner, which usually reduces the noise. In addition, there can be different operation modes for only offset, only stepping, or combination of the two.
- It is possible to measure the positioner capacitance using `ANC300.get_capacitance()`, which is useful in identifying breaks or shorts in the wiring or faults in the piezos. By default, this method simply returns the last measured value. To re-measure, call it with `measure=True`. Note that after the measurement is done, the axis is automatically disabled, and needs to be enabled explicitly:

```
>> atc = ANC300("COM5")
>> atc.get_capacitance(1, measure=True) # get the capacitance (in F) on the first
↪ axis; the method waits until the measurement is done (about 1s)
200E-9
>> atc.is_enabled(1)
False
```

Note that this is also the only way to know if there is an actual positioner connected to the given control module.



## Attocube ANC350

This controller is aimed at closed-loop (i.e., with position readout) positioners. It can control up to 3 positioners.

The device class is `pylablib.devices.Attocube.ANC350`.

## Software requirements

The controller has USB and Ethernet modes. USB mode requires a driver supplied with the controller. The communication is done via `PyUSB`, which means that it does not require any additional Attocube DLLs, although you might need to install `libusb` (see `PyUSB` for more details). Ethernet control is supplied as an additional purchasable option and can be configured using the supplied Daisy control software.

This device has only been tested with a USB connection.

## Connection

When using a USB connection, the device is identified by its index among all the connected ANC350 devices. To get the total number of devices, you can use `Attocube.get_usb_devices_number_ANC350`:

```
>> from pylablib.devices import Attocube
>> Attocube.get_usb_devices_number_ANC350()
2
>> atc1 = Attocube.ANC350() # use 0 index by default
>> atc2 = Attocube.ANC350(1)
>> atc1.close()
>> atc2.close()
```

Ethernet connection should work in the same manner as any other similar devices, i.e., the address and, possibly, the port should be provided.

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The controller is inherently multi-axis, hence it always take the axis as the first argument. The axes are numbered 0 through 2. You can check if the slide is connected to the given axis using `ANC350.is_connected()`.
- Different axes can be enabled and disabled (i.e., connected or grounded) using `ANC300.enable_axis()` and `ANC300.disable_axis()`. Disabling an axis completely shuts off the connection to the positioner, which usually reduces the noise.
- It is also possible to control the sensor voltage using `ANC350.get_sensor_voltage()/ANC350.set_sensor_voltage()` methods. Reducing this voltage lowers the heating produced by the sensor, which becomes especially important at very low (<1K) temperatures.
- The most important stepping parameters are step voltage amplitude and step frequency (number of steps per second). These can be controlled with, correspondingly, `ANC350.get_voltage()/ANC350.set_voltage()` and `ANC350.get_frequency()/ANC350.set_frequency()`.
- It is possible to measure the positioner capacitance using `ANC350.get_capacitance()`, which is useful in identifying breaks or shorts in the wiring. By default, this method simply returns the last measured value. To re-measure, call it with `measure=True`.



- Fine positioning is performed using the position readout and the feedback loop. Then a `move_to/move_by` command is issued, this feedback loop is activated, and the positioner tries to reach and stay at the current position. You can use `ANC350.is_target_reached()` to check if the target is reached, `ANC350.get_target_position()` to get the target, and `ANC350.get_precision()/ANC350.set_precision()` to control the target precision.
- In addition, there is a method `ANC350.move_by_steps()`, which mimics `ANC300.move_by()` by moving for a given number of steps instead of a given distance. However, due to implementation limitations, this method is synchronous, i.e., it waits until all steps are performed. Nevertheless, `ANC350.jog()` is still asynchronous.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

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## Thorlabs APT/Kinesis devices

Thorlabs has a variety of APT/Kinesis devices for various motion-related functionality (mostly motor controllers and piezo drivers), which share the same API. The library uses an older and more low-level APT protocol to communicate with these devices. So far it has been only implemented for motor controllers and some *specialized devices* and tested with KDC101, KST101, K10CR1, and BSC201 motor controllers, KIM101 piezo motor controller, KPZ101 piezo output controller, and TPA101 quadrature sensor controller.

The main device classes are `pylablib.devices.Thorlabs.BasicKinesisDevice` for a generic Kinesis/APT devices `pylablib.devices.Thorlabs.KinesisMotor` aimed at motor controllers such as K10CR1 or KDC101, `pylablib.devices.Thorlabs.KinesisPiezoMotor` for piezo drivers such as KIM and TIM, and `pylablib.devices.Thorlabs.KinesisPiezoController` for piezo controllers such as KPZ and TPZ.

## Software requirements

The connection is done using Thorlabs APT protocol, so it needs the corresponding APT drivers. Pylablib communicates directly with the FTDI USB-to-RS232 using `pyft232` chip inside the controller, so it bypasses most of the Thorlabs software. This means that it does not need any Thorlabs-supplied DLLs, but it also means that it can not work with the simulated devices, since these are simulated on a level above the direct serial communication.

In some cases `pyft232` library can not find the required `ftd2xx.dll` library, which leads to an error. There are several ways to get around this. First, you can install the FTDI drivers from the [manufacturer's website](#). Setup executable for Windows automatically places the necessary DLL into the System32 folder, where `pyft232` can discover them. Alternatively, you can copy the DLLs there yourself from the Thorlabs APT installation. Their default location is Program Files\Thorlabs\APT\Drivers\APT\USB Driver\amd64 for 64-bit version or Program Files\Thorlabs\APT\Drivers\APT\USB Driver\i386 for 32-bit version. Note that in the first case the file is called `ftd2xx64.dll`, and you will need to rename it to `ftd2xx.dll` when copying to the System32 folder.

## Connection

On Windows devices are identified by their address, which correspond to their serial numbers. To get the list of all the connected devices, you can use `Thorlabs.list_kinesis_devices`:

```
>> from pylablib.devices import Thorlabs
>> Thorlabs.list_kinesis_devices()
[('27500001', 'Kinesis K-Cube DC Driver')]
>> stage = Thorlabs.KinesisMotor("27500001")
>> stage.close()
```

On Linux they directly appear as virtual serial ports, e.g., `/dev/ttyUSB0`. Hence, there you need to identify which device file corresponds your device (e.g., by unplugging and plugging it back in to see which device shows up). After that, you can use this name as the device address:

```
>> from pylablib.devices import Thorlabs
>> stage = Thorlabs.KinesisMotor("/dev/ttyUSB0")
>> stage.close()
```

Note that on Linux `Thorlabs.list_kinesis_devices` will not produce a correct list, since it uses a different API. In the worst case, it can crash the process.

## Operation

### Standard motors

This controller has several features and differences compared to most other stages and sliders:

- There are two different classes of devices which require slightly different communication approach: generic USB devices and rack-bay devices. These are hard to detect a priori, so by default generic USB device (which covers the majority of equipment) is assumed. If this assumption is incorrect, the communication becomes impossible, and an attempt to connect to the device raises a communication error `ThorlabsBackendError: backend exception: 'read returned less data than expected' ('read returned less data than expected')`. If you experience this error, you should first power-cycle the device, as it often gets stuck in a non-communicable state, and then double-check that the standard Thorlabs software (Kinesis or APT) can detect and control it. If this is the case, you should supply `is_rack_system=True` to the controller:

```
stage = Thorlabs.KinesisMotor("70000001", is_rack_system=True)
```

- There are several different ways to specify the stage calibration, which are controlled by the `scale` parameter supplied upon the connection. By default (`scale = "step"`), it accepts and returns position in motor steps, velocity in steps/s and acceleration in steps/s<sup>2</sup> (scaling coefficients for the latter two are determined from the controller model). If `scale = "stage"`, the class attempts to autodetect the stage and use meters or degrees instead of steps; in addition you can supply the stage name (e.g., "MTS25-Z8") as a scale instead of relying on the autodetection. If there is no calibration for the stage that you have, you can instead supply a single scaling factor, which specifies the number of steps per physical unit (e.g., for "MTS25-Z8" stage and mm units, one would supply `scale = 34304`). The stage scaling can be obtained from the APT manual. Finally, one can supply a 3-tuple of scales for position, velocity and acceleration (all relative to the internal units). The details are given in the APT manual. To ensure that the units have been applied and/or autodetected correctly, you can use `KinesisMotor.get_scale()`, `KinesisMotor.get_scale_units()` and `KinesisMotor.get_stage()` methods.
- By default, the controllers are treated as single-axis. If several axes are supported, they can be specified using `channel` argument in the corresponding methods such as `move_to` or `get_status`. In addition, you can specify the number of channels using `KinesisMotor.set_supported_channels()` method, in which case settings `channel="all"` in the method would act on all the channels.
- The motor power-up parameters for homing, jogging, limit switches, etc., can be different from the parameters showing up in the APT/Kinesis controller. This can lead to problems if, e.g., homing speed is too low, so the motor appears stationary while homing. You should make sure to check those parameters using `KinesisMotor.get_velocity_parameters()`, `KinesisMotor.get_jog_parameters()`, `KinesisMotor.get_homing_parameters()`, `KinesisMotor.get_gen_move_parameters()`, and `KinesisMotor.get_limit_switch_parameters()`.

## Piezo motors

This controller has several features and differences compared to most other stages and sliders:

- The controllers are treated as multi-axis. However, to be compatible with other Kinesis motor, the channel argument is not required, and it defaults to the currently selected “default” channel (1 in the beginning). To control different channels, you can either supply `channel` argument explicitly, or specify a different default channel using `KinesisPiezoMotor.set_default_channel()` or `KinesisPiezoMotor.using_channel()`.
- The motor power-up parameters for jogging and drive can be different from the parameters showing up in the APT/Kinesis controller. This can lead to problems if, e.g., speed is too low. You should make sure to check those parameters using `KinesisPiezoMotor.get_drive_parameters()` and `KinesisPiezoMotor.get_jog_parameters()`.
- Even open-loop controllers support absolute positioning, which is achieved simply by counting steps in both directions. However, unlike stepper motors or encoders, these steps can be different depending on the direction, position, instantaneous load, speed, etc. Hence, the absolute positions quickly become unreliable. It is, therefore, recommended to generally use relative positioning using `KinesisPiezoMotor.move_by()` method.

## Piezo controllers

This controller acts more as a voltage amplifier than as a stage. Therefore, it does not have any motion-related commands (such as `move_to`), and instead is mainly operated through `KinesisPiezoController.enable_channel()` and `KinesisPiezoController.set_output_voltage()` methods to control the output. In addition, it supports controlling the full output range (`KinesisPiezoController.set_voltage_range()`) and the voltage source (`KinesisPiezoController.set_voltage_source()`).

## Quadrature detector

These are fairly different from the other discussed devices, since they are more related to sensors than to motors. This controller takes signal from a quadrature photodetector and implements a PI control loop to feed back to some control device (e.g., a piezo driver or a galvo mirror). Hence, all of its methods are fairly distinct from the usual motors. Nevertheless, it is described here, since it still belongs to the APT/Kinesis family of devices and shares their detection and connection approach. The device is implemented in the `pylablib.devices.Thorlabs.KinesisQuadDetector` class.

The operation is fairly straightforward: it implements control of PID parameters, output parameters (such as limits), operation mode (open/close loop), allows for reading current state and setting outputs in the open-loop mode.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

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## Thorlabs Elliptec devices

Thorlabs has a line of basic resonant piezoelectric motor stages from Elliptec, which include several rotational and linear stages and feature step-motion and position readout. The library has been tested with ELL18 and ELL14 rotational mounts.

The main device class is `pylablib.devices.Thorlabs.ElliptecMotor`.

## Software requirements

The connection is done using a USB connection together with a built-in USB-to-RS232 chip. It is automatically recognized as a serial port, and no additional software is required. In case the device is not recognized as a serial port, you can fix it by installing freely available [Thorlabs Elliptec software](#).

## Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Thorlabs
>> stage = Thorlabs.ElliptecMotor("COM5")
>> stage.close()
```

## Operation

These devices have several features and differences compared to most other stages and sliders:

- There is a possibility to have several (up to 16) devices connected to the same controller board (i.e., the same serial port address) using bus distributor. However, since they all use the same serial port, they are all controlled from a single [ElliptecMotor](#) instance. Hence, in order to refer to specific devices, each communication requires an address (integer from 0 to 15), which is specified by `addr` argument available in almost all methods. When this argument is `None` (which is the default value), the so-called default address is used, which can be accessed via [ElliptecMotor.get\\_default\\_addr\(\)](#) and [ElliptecMotor.set\\_default\\_addr\(\)](#) methods. By default, all connected devices are discovered up the connection, and the first available devices is used as default; therefore, if only a single devices is connected, `addr` argument does not have to be used.
- Compared to most motor controllers, Elliptec devices have some limitation related to their inability to communicate while the motor is moving. Therefore, there are no methods to query whether the motor is moving, or stop the motion once initiated. To address that and to simplify the library and the user code, all motion-related methods ([ElliptecMotor.move\\_to\(\)](#), [ElliptecMotor.move\\_by\(\)](#), and [ElliptecMotor.home\(\)](#)) are made synchronous, i.e., the execution is paused until the motion is complete. Note that this is true even when several devices are connected to the same port.
- There are several different ways to specify the stage calibration, which are controlled by the `scale` parameter supplied upon the connection. By default (`scale = "stage"`), the internal device calibration is used, so all of the positions are expressed in device-specific units (deg or mm). If `scale = "step"`, all of the position are specified in internal device steps instead. Finally, if `scale` is a number, it is the proportionality coefficient between the position units and the internal steps, i.e., the position in user-defined units is multiplied by it to specify the position in steps. The scale for individually addressed devices can be set using [ElliptecMotor.get\\_scale\(\)](#) and [ElliptecMotor.set\\_scale\(\)](#) methods.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

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## Newport Picomotor controller

Newport Picomotor is a series of actuators, usually in a screw format, based on the slip-stick piezo actuation mechanism (similar to, e.g., Attocubes). Operating them requires a driver/controller to output specific voltage pulses. The basic modern open-loop controller is Newport 8742, which can drive up to 4 actuators (but only one at a time), supports connection via USB or Ethernet, and can be daisy-chained to communicate with several controllers through one connection. The class has been tested with this controller and a single standard actuator.

The device class is `pylablib.devices.Newport.Picomotor8742`.

## Software requirements

The controller has two communication modes: USB, and Ethernet. USB mode requires a driver supplied with the freely available [PicomotorApp software](#), while Ethernet connection works like any other networks device and does not require any additional software. The controller has been tested both with USB and Ethernet communication modes.

## Connection

When using the USB connection, the device is identified by its index, starting from 0. To get the number of connected devices, you can use `Newport.get_usb_devices_number_picomotor`:

```
>> from pylablib.devices import Newport
>> Newport.get_usb_devices_number_picomotor()
2
>> stage1 = Newport.Picomotor8742()
>> stage2 = Newport.Picomotor8742(1)
>> stage1.close()
>> stage2.close()
```

Ethernet connection requires a host name or an IP address. Both can be set up by first connecting the device via USB or by using the PicomotorApp software (in the Setup -> Ethernet menu). After that, they can be supplied to the class instead of index:

```
>> from pylablib.devices import Newport
>> stage1 = Newport.Picomotor8742("8742-12345") # by default, all host names start with
↳ 8742
>> stage1.close()
```

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The controller is inherently multi-axis, hence it always take the axis as the first argument. The axes are labeled numerically starting from 1 (i.e., 1, 2, 3, and 4). The list of all axes is related to the exact controller, an can be obtained using `Picomotor8742.get_all_axes()`.
- There is an option to auto-detect motors and their kind using `Picomotor8742.autodetect_motors()` method. However, since it involves stepping the motor, it usually makes more sense to detect them once and then store them into the non-volatile (i.e., power-independent) memory using `Picomotor8742.save_parameters()`.
- Even open-loop controllers support absolute positioning, which is achieved simply by counting steps in both directions. However, unlike stepper motors or encoders, these steps can be different depending on the direction,

position, instantaneous load, speed, etc. Hence, the absolute positions quickly become unreliable. It is, therefore, recommended to generally use relative positioning using `Picomotor8742.move_by()` method.

- As mentioned above, the controller support daisy-chaining using RS-485 connections. It allows to connect several controllers together while still only using a single PC connection. In this case, it is recommended to supply `multiaddr=True` upon connecting to the device. If, in addition `scan=True` is set (default), then upon connection the controller scans for all other connected devices, resolves their address conflicts, and builds the list of the available addresses (address is a number between 1 and 31). The list can later be read using `Picomotor8742.get_addr_map()`, and the network rescanned using `Picomotor8742.scan_devices()`. To refer to a specific device, its address should be specified using `addr` parameter of a method; by default it is set to `None`, which selects the device connected to the PC.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

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## Arcus Performax positioners

Arcus has several motor controllers and drivers, which are mainly different in their number of axes, communication possibilities, and driving function. They are also distributed under different names, e.g., Nippon Pulse America (NPA) or Newmark Systems. However, the models nomenclature is the same: there is 4EX for 4-axis controllers with USB and RS485 connection, 2EX/2ED for 2-axis controllers with USB and RS485 connections, and 4ET for 4-axis controllers with Ethernet connection. The class has been tested with 4EX and (partially) 2ED controllers with USB and RS-485 connectivity mode, but other controllers mentioned above should also work.

The main device classes are `pylablib.devices.Arcus.Performax4EXStage` for 4-axis controllers, `pylablib.devices.Arcus.Performax2EXStage` for 2-axis controllers, and `pylablib.devices.Arcus.PerformaxDMXJSASStage` for simple single-axis controller (DMX-J-SA). In addition to a different number of axes, they have several syntax differences, so one can not substitute for the other.

In addition, there is also a generic Performax stage class `pylablib.devices.Arcus.GenericPerformaxStage`, which implements only the most basic functions: ASCII communication with the device and basic methods such as device name request. It can be used with new or not currently supported Arcus stages to directly control them using the ASCII control language (usually described in the stage manual).

## Software requirements

The controller has several communication modes: USB, RS485, and Ethernet. USB mode requires a driver supplied with the operation software: [Arcus Drivers and Tools](#), [Performax Series Installer](#), and [Performax USB Setup](#) (all obtained at [Arcus website](#)). Installing all three seem to be sufficient. Once the appropriate USB drivers are installed, one can connect the device directly via its USB port and use the manufacturer DLLs `PerformaxCom.dll` and `SiUSBXp.dll` to communicate with the device. They can be obtained on the manufacturer's [website](#) and placed in the folder with the script, or in the System32 Windows folder. If the DLL is located elsewhere, the path can be specified using the library parameter `devices/dlls/arcus_performax`:

```
import pylablib as pll
pll.par["devices/dlls/arcus_performax"] = "path/to/dll"
from pylablib.devices import Arcus
stage = Arcus.Performax4EXStage()
```

**Warning:** There appear to be some issues for USB-controlled devices with Python 3.6 which result in out-of-bounds write, memory corruption, and undefined behavior. Hence, Python 3.7+ is required to work with this device.



RS-485 connection does not require any device-specific drivers or DLLs, but it does need RS-485 controller connected to the PC. Such controllers usually show up as virtual COM ports, and they typically do not need any additional drivers.

## Connection

When using the USB connection, the device is identified by its index, starting from 0. To get the list of all the connected devices, you can use `Arcus.list_usb_performax_devices`:

```
>> from pylablib.devices import Arcus
>> Arcus.list_usb_performax_devices()
[(0, '4ex01', 'Performax USB',
  '\\\\?\\usb#vid_1589&pid_a101#4ex01#{xxxxxxxx-xxxx-xxxx-xxxx-xxxxxxxxxxxx}', '1589',
  ↪ 'a101'),
 (1, '4ex21', 'Performax USB',
  '\\\\?\\usb#vid_1589&pid_a101#4ex21#{xxxxxxxx-xxxx-xxxx-xxxx-xxxxxxxxxxxx}', '1589',
  ↪ 'a101')]
>> stage1 = Arcus.Performax4EXStage()
>> stage2 = Arcus.Performax2EXStage(idx=1)
>> stage1.close()
>> stage2.close()
```

When using the RS-485 connection, you need to specify the serial port corresponding to your RS-485 connection and, possibly, its baud rate:

```
stage = Arcus.Performax4EXStage(conn = "COM5")
stage2 = Arcus.Performax4EXStage(conn = ("COM5", 38400)) # specify a baud rate
```

The baud rate is 9600 by default, which is the standard value for the controllers. However, it can be changed using `Performax4EXStage.set_baudrate()` method, in which case you would need to explicitly specify it during the next connection.

In RS-485 mode `idx` parameter is still used, and it specifies the device number connected to this controller. By default this number is 0, and it can be queried (using USB connection) via `Performax4EXStage.get_device_number()`. It can also be set using `Performax4EXStage.set_device_number()`, although the changes takes effect only after the device is power cycled. Although in principle `idx` can be used to distinguish several Arcus controllers connected to the same bus (i.e., sharing the same RS-485 COM port), currently only single device connection is supported.

To switch between USB and RS-485 control modes, you need to plug or unplug USB connection. It is strongly recommended to power cycle the device after that, since otherwise it might stop responding to RS-485 commands.

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The 4-axis and 2-axis controllers are inherently multi-axis, hence they always take the axis as the first argument. The axes are labeled with letters "x", "y" for a 2-axis version, or "x", "y", "z", "u" for a 4-axis one. The list of all axes is related to the exact controller, and can be obtained using `Performax4EXStage.get_all_axes()`. A single-axis controller does not take an axis argument.
- Different axes can be enabled and disabled using `Performax4EXStage.enable_axis()`. Note that disabled axes still behave the same as the enabled ones; e.g., their position will increment as usual, when `move_to` is called. This can lead to some confusion, as the axis appears mostly operational, but the motor does not move.
- In the default controller configuration the limit errors are enabled. In this case, once a single axis reaches the limit switch during motion, it is put into an error state, which immediately stops this and all other axes. Any further

motion command on this axis will raise an error, although it is still possible to restart motion on other axes. The axis motion can only be resumed by calling `Performax4EXStage.clear_limit_error()`. If, however, limit errors are disabled, then only the axis which reached the limit is stopped, and all other axes are unaffected. Furthermore, the motion on the offending axis can be resumed without clearing its error status. In many cases the default limit error behavior is undesirable, so the class turns it off upon connection. It can be subsequently turned on and off using `Performax4EXStage.enable_limit_errors()`, and checked using `Performax4EXStage.limit_errors_enabled()`.

- Since simplified single-axis controller (DMX-J-SA) always has limit errors disabled, its behavior is specified a bit differently. Upon connection you can specify `autoclear` argument (True by default), which indicates that before every movement command the limit error should be automatically cleared.
- The controllers also have analog and digital inputs and digital outputs, which can be queried and set with the corresponding commands.
- The controller has an option to connect an encoder for a separate position readout. By default, all of the commands (e.g., for moving, getting position, getting current speed, etc.) still work in the step-counting mode, and the encoder values are only accessed via `Performax4EXStage.get_encoder()/Performax4EXStage.set_encoder_reference()`. In principle, there is a closed-loop mode call `StepNLoop`, but it is not currently supported in the code.
- The built-in motion command has 2 modes: relative and absolute. The code sets the absolute mode on connection and assumes it in all commands. However, if the mode changes for any reason, the move commands will stop working properly.

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**Note:** General stage communication concepts are described on the corresponding [page](#)

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## Trinamic TMCx110 controller

TMCx110 are universal stepper motor controller from Trinamic (currently Analog Devices), which include single-axis TMCx110 and multi-axis TMCx3110 and TMCx6110. It provides multiple connection options, but so far has only been tested with USB connection.

The main device classes are `pylablib.devices.Trinamic.TMCx110` for multi-axis devices and `pylablib.devices.Trinamic.TMC1110` for a single-axis TMCx110 (TMCx110 can also be used with TMCx1110, but many of the device variable will be dictionaries `{axis: value}` instead of single values).

## Software requirements

USB connection needs drivers, which are supplied with the freely-available [TMCL-IDE](#). With those drivers installed (and even frequently already without them), the controllers show up as virtual COM ports. Note that when several devices are connected, they sometimes get assigned conflicting (i.e., overlapping) COM ports. In this case, you might need to manually reassign these in the Device Manager.



## Connection

Since the devices are identified as virtual COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Trinamic
>> stage1 = Trinamic.TCMx110("COM5")
>> stage2 = Trinamic.TCM1110("COM8")
>> stage1.close()
>> stage2.close()
```

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The controller allows one to control the number of microsteps per step using `TCM1110.get_microstep_resolution()` and `TCM1110.set_microstep_resolution()`. Hence, the calibration of the real position to the controller readout position depends on this resolution. Furthermore, changing this resolution does not affect the step counter, meaning that changing it, performing a move, and changing it back will result in a different position. Hence, it is not recommended to change it after homing or referencing the position.
- Similarly, the controller has variable frequency divisors, which control the ratio between internal and real units for the velocity and the acceleration. They are set up together with the maximal velocity and acceleration using `TCM1110.setup_velocity()` and `TCM1110.get_velocity_parameters()`, and the conversion factors can be obtained using `TCM1110.get_acceleration_factor()` and `TCM1110.get_velocity_factor()`.
- The device has an option of controlling maximal output current using `TCM1110.setup_current()` and `TCM1110.get_current_parameters()`. Change them carefully, since the values which are too large can damage the motor. Also take into account, that the currents are defined relative to the maximal output current, which is controlled using the physical jumper on the board (on TCM-1110).
- The only real difference between `pylablib.devices.Trinamic.TCMx110` and `pylablib.devices.Trinamic.TCM1110` is in how axis parameters are handled in device variables. In `TCM1110` the values are turned as scalars, e.g., `stage.dv["position"]` can simply return 1234. In contrast, `TCMx110` returns dictionary, so `stage.dv["position"]` will return `{0: 1234}`.

---

**Note:** General stage communication concepts are described on the corresponding *page*

---

## SmarAct positioners

SmarAct has multiple different controller covering different slider kinds. So far only simple controllers (CU/HCU/SCU) are implemented.

## SmarAct CU/HCU/SCU

This is a simple controller, which is mostly aimed at open-loop (i.e., no position readout) positioners. It can control up to 3 axes, and connects to the PC via the USB port.

The device class is `pylablib.devices.SmarAct.SCU3D`. Currently only open-loop controllers are supported.

## Software requirements

The controller shows up as a virtual COM port, and it has a standard FTDI chip, so it does not need any special drivers. However, to communicate with the device, it still needs `SCU3DControl.dll` library. It is supplied on a CD together with the device, although it might also be possible to request it from SmarAct.

## Connection

The devices are identified by their index starting from 0. To get the list of all the connected devices, you can use `SmarAct.list_scu_devices`:

```
>> from pylablib.devices import SmarAct
>> SmarAct.list_scu_devices()
[TDDeviceInfo(device_id=0, firmware_version='1.3.0.0', dll_version='4.3.0.0')]
>> stage = SmarAct.SCU3D(idx=0) # connect to the first device in the list
>> stage.close()
```

Due to the manufacturer’s API organization, it is currently only possible to “reserve” all connected stages of the same type simultaneously in one application. This means that no other application can connect to any of the stages as long as at least one stage is being controlled (though it does not make any difference if only one stage is connected).

In addition, currently there is no check on whether the stage is already controlled in the other part of the code. This is in contrast with the vast majority of the devices, which issue a unique handle making it impossible to create two different device objects even within the same application. Hence, one needs to be careful to not connect to the same device twice, which can lead to confusing behavior.

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The motion is generally executed in “macrosteps”, which is a sequence of several “microsteps” with a given amplitude, frequency, and number. A single macrostep with the defined parameters can be performed with `SCU3D.move_macrostep()`, while `SCU3D.move_by()` executes a series of these macrosteps with one of the predefined sizes (from 0 to 20). These sizes are configured to roughly correspond to the step sizes selectable by the controller, although the agreement is not exact.

## SmarAct MCS2 stages

This is an advanced controller, which can control multiple open-loop and closed-loop stages using multiple sensor modules. It connects to the PC via the USB or the Ethernet port.

The device class is `pylablib.devices.SmarAct.MCS2`. It has been tested with an Ethernet-connected MCS module with several SLx stages.

## Software requirements

The controller requires libraries supplied with the SmarAct MCS2 software, which is usually distributed with the device. The required DLL is called `SmarActCTL.dll` and is located in the MCS2 folder (either MCS/SDK/lib64 for 64-bit systems). By default, pyLabLib searches for these DLLs in the default MCS2 software location (C:/SmarAct/MCS2), in the folder defined by the corresponding environment variable upon installation (MCS2\_SDK), as well as in the folder containing the script. If the DLLs are located elsewhere, the path can be specified using the library parameter `devices/dlls/smaract_mcs2`:

```
import pylablib as pll
pll.par["devices/dlls/smaract_mcs2"] = "path/to/MCS2/dlls"
from pylablib.devices import SmarAct
stage = SmarAct.MCS2("network:sn:MCS2-00000001")
```

## Connection

The devices are identified by their locator string, which may look like, e.g., `"network:sn:MCS2-00000001"` or `"usb:sn:MCS2-00000001"`. To get the list of all the connected devices, you can use `SmarAct.list_mcs2_devices`:

```
>> from pylablib.devices import SmarAct
>> SmarAct.list_mcs2_devices()
["usb:sn:MCS2-00000123"]
>> stage = SmarAct.MCS2("usb:sn:MCS2-00000123")
>> stage.close()
```

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The provided class implements the basic functionality required for the regular levels of automation: movement, accessing position and status, setting up basic parameters (velocity, acceleration, step frequency, etc.), homing. However, it does not cover more advanced and rarely used functions like details of the sensor operation, auxiliary IO, triggering, operation modes (normal, low noise, etc.), PID parameters, and so on. These can still be accessed using `MCS2.get_property()` and `MCS2.set_property()` methods, but the interpretation of the property values is up to the user.

---

**Note:** General stage communication concepts are described on the corresponding [page](#)

---

## Physik Instrumente (PI) controllers

Physik Instrumente produces a variety of piezo, servo, and slider controller. So far, only PI E-515 and PI E-516 are supported and tested via a standard serial connection.

The main device classes are `pylablib.devices.PhysikInstrumente.PIE515` and `pylablib.devices.PhysikInstrumente.PIE516`.

## Software requirements

The devices provide a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

Note that these devices frequently require cross-cable (also called null-modem cable), in which connections between Rx and Tx lines are switched. In addition, one might need to activate RS-232 communication in the front panel menu, as otherwise the device would not respond.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import PhysikInstrumente
>> stage1 = PhysikInstrumente.PIE516("COM5")
>> stage2 = PhysikInstrumente.PIE516("COM8")
>> stage1.close()
>> stage2.close()
```

## Operation

These controllers has several features and differences compared to most other stages and sliders:

- The controllers support either servo (position feedback) or direct voltage output modes, controlled with `PIE516.enable_servo()` method. In the servo mode they are more similar to a stage controller, and you can use, e.g., `PIE516.move_to()` and `PIE516.stop()` (only for E-516) methods. In the direct voltage mode you can use `PIE516.set_voltage()` to set the voltage directly.
- The controllers only accepts commands from the PC when it is in the “online” (i.e., remote) mode, in which case external voltage controls are ignored. This mode is enabled automatically upon connection if `auto_online=True` is supplied upon creation (default), and can be connected via `PIE516.enable_online()` method. Note that in this case manual servo switches should be turned off, since otherwise the device is permanently in the servo mode.
- PI E-515 bring additional complications due to its mechanism of switching between the manual and online modes:
  - First, the online mode is only accessible when the servo mode switches on the front panel are off. At the same time, even when online mode is not enabled (and the voltages/positions can not be controlled remotely), it is still possible to switch the servo mode on and off remotely, so one must be careful when calling `PIE515.enable_servo()`.
  - Second, when switching to the online mode, all of the voltages and positions are set to the last time they were updated (or zero, if they have not been changed since the device was turned on). It is possible to set the remote voltages to match the local ones before switching the modes, which is done automatically when

`safe=True` is supplied to `PIE515.enable_online()`. The same can not be done for servo positions, since these can only be changed when the servo mode is on.

- Finally, when the online mode is turned back off, the output voltages go back to the values set by manual knobs, which can be different from the current remote settings.

As a result, one should expect and look out for sudden changes in the stage positions when switching between online and offline modes, and when switching the servo on and off.

---

**Note:** General stage communication concepts are described on the corresponding [page](#)

---

## Standa motorized stages

Standa produces a variety of motorized stages and positions, which are generally controlled by a single controller model 8SCM4 (older version) or 8SMC5 (newer version).

The main device class are `pylablib.devices.Standa.Standa8SMC`. The code has been tested with 8SMC4-USB single-axis controller and 8MT167-25 stepper motor stage.

## Software requirements

The controllers have a built-in USB-to-RS232 adapter, which is automatically recognized as a serial port by the OS, so no additional software is required.

## Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Standa
>> stage = Standa.Standa8SMC("COM3")
>> stage.close()
```

## Operation

This controller has several features and differences compared to most other stages and sliders:

- The controllers provide a large set of methods for checking and adjusting various motion parameters, controlling different accessories, etc. So far only a basic subset of these commands is implemented, which allows one to start and stop the motion, home the stage, set up basic velocity parameters, and query the status. If you need advanced functionality, you can examine the list of commands in the [documentation](#) and implement them in your code using `Standa8SMC.query()` method.
- All commands dealing with distances (e.g., moving, getting position, velocity, etc.) use internal units. For DC motors these are steps (derived from the rotational encoder), while for stepper motors these are microsteps, whose resolution can be found using `Standa8SMC.get_stepper_motor_calibration()`. This means that, e.g., given a stepper motor with 200 steps per revolution and 256 microsteps per step, one can rotate it by a full turn (before taking a possible gearbox into account) by calling `stage.move_by(200*256)`.
- Some stages can come with a built-in linear encoder. In this case, the position can be accessed both using `Standa8SMC.get_position()` method like for all other stages, and using `Standa8SMC.get_encoder()` method. If there is not linear encoder, `Standa8SMC.get_encoder()` will return zero.

## 2.2.4 Basic sensors

Basic concepts are described at the *basic sensors communication page*.

Currently supported sensors:

- *HighFinesse*: laser wavelength meters. Tested with WS6 and WS7 USB-controlled devices.
- *Ophir*: optical power and energy meters. Tested with Ophir Vega.
- *Thorlabs*: optical power and energy meters. Tested with PM160.
- *Lakeshore*: temperature sensors. Tested with Lakeshore 218.
- *Cryocon*: temperature sensors. Tested with CryoCon 14C.
- *Cryomagnetics*: liquid nitrogen or helium level sensor. Tested with LM-500 and LM-510 sensors.
- *Pfeiffer*: pressure gauges. Tested with TPG261 and DPG202 controllers.
- *Leybold*: pressure gauges. Tested with ITR90 gauge.
- *Kurt J. Lesker*: pressure gauges. Tested with KJL300 gauge.
- *Agilent*: pressure gauges. Tested with XGS-600 controller and FRG700 gauge.
- *Thorlabs quadrature detector controller*. Tested with TPA101.
- *Keithley multimeters*. Tested with model 2110.
- *Voltcraft multimeters*. Tested with VC-7055BT and VC880.

---

**Note:** General device communication concepts are described on the corresponding *page*.

---

## Basics of sensors communication

### Basic example

Basic sensors usually only implement a handful of functions related to reading out the measurements (possibly on different channels) and setting up measurements modes:

```
>> gauge = Pfeiffer.TPG260("COM1") # connect to the gauge
>> gauge.enable(1) # enable the first channel (usually it's already enabled)
>> gauge.get_pressure() # read pressure at the default channel (1)
100E3
>> gauge.close()
```

## Application notes and examples

Here we talk more practically about using pylablib to perform commons sensor tasks.

## Readout

The main readout methods almost always start with `get_` prefix, e.g., `get_pressure`, `get_temperature`, or `get_level`. In some cases there would be two different measurement modes: one which just reads the latest measurement result, and one which initializes the measurement, waits until it's done, and returns the result. These two approaches may be implemented differently in different devices, and it is addressed in their description:

```
>> meter = Cryomagnetics.LM500("COM1")
>> meter.get_level(1)  # immediately return the latest reading
20.0
>> meter.get_level(1)  # return the same reading
20.0
>> meter.measure_level(1)  # initialize a new measurement; takes some time
19.8
```

## Non-numerical values

In some cases the readout method would return a non-numerical values. This usually happens when the sensor readings are outside of its range, or if it is in a wrong state (off, warming up, error, etc.) These cases are documented in the querying method description:

```
>> meter = Ophir.VegaPowerMeter("COM1")
>> meter.get_power()  # power is higher than the current range
'over'
>> meter.set_range_idx(0)  # set the maximal power range
>> meter.get_power()  # now the reading is numerical
10E-3
```

## Units

Unless absolutely necessary and obvious, all the readout values are specified in SI units (even, e.g., laser frequency in Hz, or pressure in Pa). In rare cases when the devices allows for selection of readout units (e.g., Pfeiffer TPG260 gauges), it only affects the displayed value, but not the results returned by the corresponding methods:

```
>> gauge = Pfeiffer.TPG260("COM1")
>> gauge.set_units("pa")
>> gauge.get_pressure()
100E3
>> gauge.set_units("mbar")
>> gauge.get_pressure()  # pressure still in Pa
100E3
>> gauge.get_pressure(display_units=True)  # pressure in display units
1000
```

## Channel selection

Some gauges support simultaneous readout on several channels. In this case, all of their methods take an additional `channel` (in most cases) argument, which specify the read channel.

The channels are usually specified by their index starting from 0 or 1, although some devices adopt more complicated labeling schemes (e.g., Lakeshore 218 temperature sensor can only assign a sensor type to a group of 4 sensors, which is labeled "A" or "B"). The exact specification is given in the specific class description.

## Currently supported sensors

- *HighFinesse*: laser wavelength meters. Tested with WS6 and WS7 USB-controlled devices.
- *Ophir*: optical power and energy meters. Tested with Ophir Vega.
- *Thorlabs*: optical power and energy meters. Tested with PM160.
- *Lakeshore*: temperature sensors. Tested with Lakeshore 218.
- *Cryocon*: temperature sensors. Tested with CryoCon 14C.
- *Cryomagnetics*: liquid nitrogen or helium level sensor. Tested with LM-500 and LM-510 sensors.
- *Pfeiffer*: pressure gauges. Tested with TPG261 and DPG202 controllers.
- *Leybold*: pressure gauges. Tested with ITR90 gauge.
- *Kurt J. Lesker*: pressure gauges. Tested with KJL300 gauge.
- *Agilent*: pressure gauges. Tested with XGS-600 controller and FRG700 gauge.
- *Thorlabs quadrature detector controller*. Tested with TPA101.
- *Keithley multimeters*. Tested with model 2110.
- *Voltcraft multimeters*. Tested with VC-7055BT and VC880.

---

**Note:** General sensor communication concepts are described on the corresponding [page](#)

---

## HighFinesse wavemeters

HighFinesse produces a variety of fiber-coupled wavelength meters. Currently pylablib only deals with WS series which uses a USB connection. The code has been tested with several WS6 and WS7 wavemeters.

The main device class is `pylablib.devices.HighFinesse.WLM`.

## Software requirements

HighFinesse employs a fairly unique control system.

First, one needs to install the control software, which is uniquely tied to a particular wavemeter and is supplied with it. In theory, software from another wavemeter might still work, but the results are not guaranteed.

Second, this control software runs an application server which processes all requests from third-party software. This means, that the main application needs to be running to perform any device communication from the code. The code has an option of automatically starting it, but on some occasions it might fail, in which case it is necessary to either manually start it, or supply the location of the executable file.



---

**Note:** The control software should keep running the whole time. As soon as it is closed, the device will raise an error.

---

Finally, one needs the DLL to communicate with this software. It is usually named `wlmData.dll`, and it is located in the main controller software folder either in `Com-Test` (for 32-bit applications) or `Projects/64` (for 64-bit applications).

## Connection

The device class makes an attempt to search for the DLL and executable in the standard installation folders, as well as use the DLL in the standard location and its executable auto-detection capabilities. However, depending on the number of installed wavemeters and their installation locations, one needs to provide up to 3 arguments on connection. First, the wavemeter ID, which simply a 1 to 5-digit number (e.g. 1234). It is used to identify the correct instance of the control software, either by searching for the correct folder, or via DLL autostart capabilities. Second, one might need to provide the path to `wlmData.dll` (either including the name, or simply the containing folder). Its location is described in the above section. Finally, you might also need to give the path to the application executable, which is located in the main installation folder and is named `wlm_ws*.exe`, where `*` is the wavemeter generation (e.g., `wlm_ws7.exe` for WS7 wavemeters). Hence, the fully qualified (and, therefore, most robust) instantiation looks like this:

```
>> import os
>> from pylablib.devices import HighFinesse
>> app_folder = r"C:\Program Files\HighFinesse\Wavelength Meter WS7 1234"
>> dll_path = os.path.join(app_folder, "Projects", "64")
>> app_path = os.path.join(app_folder, "wlm_ws7.exe")
>> wm = HighFinesse.WLM(1234, dll_path=dll_path, app_path=app_path)
>> wm.close()
```

A unique property of this device is the ability to control it simultaneously from several applications. Keep this in mind, since it might cause confusion or strange results if the control attempts are not synchronized.

**Warning:** Communication with several simultaneously running wavemeters from a single application has not been tested, and might not work correctly.

## Operation

The operation of the wavemeter is fairly straightforward, but there is a couple of points to keep in mind:

- By default, the main measurement functions (`WLM.get_frequency()` and `WLM.get_wavelength()`) raise an error on over- or under-exposure. If this is undesirable (e.g., the laser has power jumps), one can instead make it return "over" or "under" on these occasions.
- The measurement result is returned immediately, but it is updated only about every 15-30ms (+ exposure time). Hence, fast consecutive calls to `WLM.get_frequency()` and `WLM.get_wavelength()` will return the same value.
- Multi-channel devices have two working modes: single-channel (when only one channel is enabled at a time) and cycling (the wavemeter constantly cycles through several channels for quasi-simultaneous measurements). Some methods only make sense in one of this modes, e.g., `WLM.set_active_channel()` only works in the single-channel mode, while `WLM.enable_switcher_channel()` only in the multi-channel mode. By default, these methods will automatically switch to the corresponding mode.
- Due to a minor control software bug, change in the exposure on some channels might not be reported until the control software is switched to the corresponding channel's exposure control tab (in the upper right cor-

ner). By default, the device class performs this switching any time the exposure value is queried, which solves the issue. However, it does take about 10ms. If it is critical, it's possible to turn off this behavior by setting `auto_channel_tab` attribute to `False`.

---

**Note:** General sensor communication concepts are described on the corresponding [page](#)

---

## Ophir power meters

Ophir produces a variety of power and energy meters with different controllers and measurement heads. The class has been tested with Ophir Vega controller with a photodiode head.

The main device classes are `pylablib.devices.Ophir.OphirDevice` for a generic device and `pylablib.devices.Ophir.VegaPowerMeter` for Vega power meter.

## Software requirements

The device provides a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5) and the baudrate, if it is different from the standard one (9600 baud):

```
>> from pylablib.devices import Ophir
>> meter1 = Ophir.VegaPowerMeter("COM5") # default connection assumes 9600 baud
>> meter2 = Ophir.VegaPowerMeter("COM6", 19200) # if the second power meter has a
↳different baudrate
>> meter1.close()
>> meter2.close()
```

## Operation

The operation of the power meter is fairly straightforward, but there is a couple of points to keep in mind:

- On the Vega controller the results can be sent at most 15 times a second. However, they are not necessarily updated at this rate, so several consecutive request might yield the same result.
- The device provides the way to change the communication baud rate. If the rate is changed, the device is automatically disconnected, and the new object needs to be instantiated with the updated baudrate.
- The device might return "over" instead of the power reading on overexposure. To fix that, you can adjust the measurement range using `VegaPowerMeter.set_range_idx()`.

---

**Note:** General sensor communication concepts are described on the corresponding [page](#)

---

## Thorlabs PM100/PM160 series power meters

Thorlabs produces several different models of power and energy meters with different controllers and measurement heads, but relatively similar interfaces. The class has been tested with PM160 standalone power VegaPowerMeter.

The main device class `pylablib.devices.Thorlabs.PM160`.

## Software requirements

The drivers for USB devices are provided in the [Thorlabs Optical Power Monitor software](#) software. PyLabLib uses NI VISA communication interface to communicate with this device. Hence, it also requires NI VISA Runtime, which is freely available from the [National Instruments website](#). Finally, to make the devices run with VISA interface, you need to run Power Meter Driver Switcher (comes with the Optical Power Monitor software) and switch all the desired power meters to PM100D mode (it is called PM100D even for other power meters such as PM160).

Devices with pure RS232 interface do not require Thorlabs software, and only need an appropriate USB-to-RS232 adapter with its own drivers.

Devices with bluetooth connection can be used on Windows via a bluetooth COM port. For that, first you need to connect the power meter to your PC by making sure it is active (i.e., the display is lit up), and then adding a new bluetooth device in Bluetooth and other devices settings (the power meter should show up in the list of discovered devices). After that, you need to open More Bluetooth options (in the panel on the right side) and navigate to the COM Ports tab. There should already be several COM ports in the list corresponding to the added power meter. You are interested in the one marked with Outgoing direction, with the name containing 'SPP' (e.g., Thorlabs PM160 4000000 'SPP'). The corresponding COM port (e.g., COM5) is the one you need to use for communication.

## Connection

Depending on the protocol used (VISA or RS232/bluetooth), you will need to supply either a VISA name (e.g., "USB0::0x1313::0x807B::400000::INSTR") or a COM port name (e.g., "COM5"), potentially with the baud rate if it is different from the standard 115200 baud (e.g., ("COM5", 19200); only applies to RS232 devices, not bluetooth):

```
>> from pylablib.devices import Thorlabs
>> meter1 = Thorlabs.PM160("USB0::0x1313::0x807B::400000::INSTR") # USB connection uses VISA interface
>> meter2 = Thorlabs.PM160("COM3") # bluetooth connection uses a COM port
>> meter1.close()
>> meter2.close()
```

## Operation

The operation of the power meter is fairly straightforward, but there is a couple of points to keep in mind:

- Bluetooth communication tends to go to a sleep mode after about a second of inactivity (i.e., lack of communication with the PC). When in this mode, it takes about a second for the device to reply to the first command, after which it switches in the active mode and replies significantly fast (about 20ms per command) until it goes back into the sleep mode. Hence, to keep the device responsive, it is important to poll it at least 2-3 times a second (e.g., using method `PM160.get_reading()` with `measure=False`, which immediately returns the currently displayed value).

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

## Lakeshore temperature sensors

Lakeshore manufactures a range of temperature sensor controllers and resistance bridges, which are also used for temperature sensing. There is some overlap between different products, but they still use fairly distinct interfaces and interaction patterns. The code has been tested with Lakeshore 218 temperature controller.

The main device class is `pylablib.devices.Lakeshore.Lakeshore218`.

## Software requirements

The device provides a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Lakeshore
>> sensor = Lakeshore.Lakeshore218("COM5")
>> sensor.close()
```

Note that the connection uses the standard which is fairly different from most RS232 controllers: 7 data bits, 1 parity bit, and 1 stop bit (as opposed to 8 data bits and no parity bit for most controllers). Hence, it is possible that not all RS232 controllers can communicate with it. In addition, they might need a null-modem (crossed Rx and Tx lines) RS232 cable.

## Operation

The operation of this temperature sensor is fairly straightforward, but there is a couple of points to keep in mind:

- Like most similar devices, querying temperature using `Lakeshore218.get_temperature()` immediately returns the most recently measured value. Re-measurement is periodically initiated by the devices itself.
- It is possible to specify custom response curves by using `Lakeshore218.set_curve_header()` and `Lakeshore218.set_curve()`. However, you need to be careful, as it overwrites the stored user curves.

---

**Note:** Basic sensors communication concepts are described on the corresponding *page*

---

## CryoCon temperature sensors

CryoCon manufactures a range of temperature sensor controllers and resistance bridges, which are also used for temperature sensing. The code has been tested with CryoCon 14C temperature controller.

The main device class is `pylablib.devices.Cryocon.Cryocon1x`.

## Software requirements

The device provides a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Cryocon
>> sensor = Cryocon.Cryocon1x("COM5")
>> sensor.close()
```

## Operation

The operation of this temperature sensor is fairly straightforward, but there is a couple of points to keep in mind:

- Like most similar devices, querying temperature using *Cryocon1x.get\_temperature()* immediately returns the most recently measured value. Re-measurement is periodically initiated by the devices itself.

---

**Note:** Basic sensors communication concepts are described on the corresponding *page*

---

## Cryomagnetics level monitor

Cryomagnetics manufactures cryogenic liquid level monitors, which are used for monitoring liquid nitrogen or helium levels inside cryostats. The two level meters supported in the package are LM-500 and LM-510; despite difference in appearance, their functionalities are very similar, so their interfaces are nearly identical.

The main device classes are *pylablib.devices.Cryomagnetics.LM500* and *pylablib.devices.Cryomagnetics.LM510*.

## Software requirements

LM-500 provides a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work. LM-510 has a USB interface with a built-in USB-to-RS232 adapter, which is automatically recognized as a serial port, so no additional software is required.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Cryomagnetics
>> sensor = Cryomagnetics.LM510("COM5")
>> sensor.close()
```

## Operation

The operation of this temperature sensor is fairly straightforward, but there is a couple of points to keep in mind:

- Upon connection the devices are automatically switched into the remote mode, which disables manual controls. If this mode is manually switched off (e.g., using Local button in LM-510), the device will no longer obey the remote commands, even though the readout would still work.
- There are no specific commands for stopping a refill or resetting the timeout state after a timed-out refill. However, both can be achieved using `LM500.reset()` method.
- Only LM-510 supports switching the automated refill option on and off using `LM510.set_control_mode()` method.
- Like most similar devices, querying the level using `LM500.get_level()` immediately returns the most recently measured value. Re-measurement is periodically initiated by the devices itself, or can be initiated manually using `LM500.start_measurement()` or `LM500.measure_level()`.

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

## Pfeiffer pressure gauges

Pfeiffer manufactures a range of pressure gauges and controllers with several different standards and communication protocols. The code has been tested with Pfeiffer TPG260 series controller (specifically, TPG261) and Pfeiffer DPG202 controller.

The main device classes are `pylablib.devices.Pfeiffer.TPG260` and `pylablib.devices.Pfeiffer.DPG202`.

## Software requirements

The devices provide a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Pfeiffer
>> gauge = Pfeiffer.TPG260("COM5")
>> gauge.close()
```

## Operation

### TPG260 series

The operation of this gauge is fairly straightforward, but there is a couple of points to keep in mind:

- On measurement error `TPG260.get_pressure()` returns None. To get the underlying issue, you can use `TPG260.get_channel_status()`

- By default, the pressure is always returned in Pa regardless of the display units. This behavior can be overridden by setting `display_units=True` in `TPG260.get_pressure()`.
- In case an error occurs, you can use `TPG260.get_current_errors()` to get the list of currently active errors and `TPG260.reset_error()` to reset them.
- This communication protocol for 350-series gauges (361, 362 and 366) is similar, so the device class should also be able to work with them. However, it has not been tested.

## DPG202/TPG202 controller

There is a variety of different controllers which implement a similar protocol: DPG202 and TPG202, as well as a variety of RS485-controlled gauges (e.g., CPT200). It is based on requesting parameters with certain 3-digit numbers. These are fairly consistent between the devices, for example, 312 stands for the software version, 740 for pressure, and 349 for the device name. However, different devices implement different subsets of these parameters. The supplied class provides a generic interface through `DPG202.get_value()` and `DPG202.comm()` methods, which, correspondingly, request or set a value of a given parameter given its number (e.g., 740) and datatype (e.g., "string", "u\_expo\_new", or "u\_short\_int"). Both of these pieces of information are usually provided in the controller or gauge manual in the `Parameter` overview (or similar-named) section. Currently the device class provides only the most basic functionality:

```
>> from pylablib.devices import Pfeiffer
>> gauge = Pfeiffer.DPG202("COM5")
>> gauge.get_pressure() # pressure in Pa
9.78E4
>> gauge.get_value(740,"u_expo_new") # request the parameter directly, yields pressure_
↳ in mBar
9.78E2
>> gauge.close()
```

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

## Leybold pressure gauges

Leybold manufactures a range of pressure gauges and controllers with several different standards and communication protocols. The code has been tested with Leybold ITR90 pressure gauge using its built-in RS232 connection.

The main device classes are `pylablib.devices.Leybold.ITR90`.

## Software requirements

The devices provide a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Leybold
>> gauge = Leybold.ITR90("COM5")
>> gauge.close()
```

## Operation

### ITR90

The operation of this gauge is fairly straightforward, but there is a couple of points to keep in mind:

- Device operates by constantly streaming its status updates. To get the most recent and most consistent data, you can use *ITR90.get\_update()*. This is also how you access the gauge status and error states.
- By default, the pressure is always returned in Pa regardless of the display units. This behavior can be overridden by setting *display\_units=True* in *ITR90.get\_pressure()*.

---

**Note:** Basic sensors communication concepts are described on the corresponding *page*

---

## Kurt J. Lesker pressure gauges

KJL manufactures a range of pressure gauges and controllers with several different standards and communication protocols. The code has been tested with KJL300 pressure gauge using its built-in RS232 connection.

The main device classes are *pylablib.devices.KJL.KJL300*.

## Software requirements

The devices provide a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import KJL
>> gauge = KJL.KJL300("COM5")
>> gauge.close()
```



## Operation

### KJL300

The operation of this gauge is fairly straightforward, but there is a couple of points to keep in mind:

- Even standard RS232 operation requires specifying the device RS485 address. IT can be specified using `addr` parameter on creation. By default, the class assumes the factory default of 1, but if it is ever changed on the device, it needs to be specified correctly.
- By default, the pressure is always returned and set in Pa regardless of the display units.

### Agilent pressure gauges

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

Among other things, Agilent manufactures a range of pressure gauges and controllers. The code has been tested with Agilent XGS-600 controller with an analog board and FRG700 gauge.

The main device class is `pylablib.devices.Agilent.XGS600`.

### Software requirements

The devices provide a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work.

## Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Agilent
>> gauge = Agilent.XGS600("COM5")
>> gauge.close()
```

## Operation

### XGS-600 series controller

The operation of this controller is fairly straightforward, but there is a couple of points to keep in mind:

- The list of pressures returned by `XGS600.get_all_pressures()` only includes the installed boards, so it will changed when boards are installed or removed. On the other hand, the order does not depend on whether gauges are connected, since it return "nochl" for any connectors without gauges.
- By default, the pressure is always returned in Pa regardless of the display units. This behavior can be overridden by setting `display_units=True` in `XGS600.get_all_pressures()`.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.5 Basic lasers

### Basic example

Basic lasers (such as pump lasers) usually only have very basic power-related functionality: turning it on and off, setting power, and controlling and/or requesting the shutter state:

```
>> laser = LaserQuantum.Finesse("COM1") # connect to the laser
>> laser.set_output_power(10.) # set 10W output power
>> laser.enable() # enable the laser
>> laser.get_output_power() # laser hasn't ramped up yet
0.1
>> time.sleep(30.) # wait until the ramp up is done
>> laser.get_output_power()
10.0
>> laser.enable(False)
>> laser.close()
```

### Lighthouse Photonics Sprout

Lighthouse Photonics Sprout laser implements the same basic functionality, with some small additions like reading the interlock status, output mode, temperatures, etc.

The device class is `pylablib.devices.LighthousePhotonics.SproutG`.

Since the device shows up as a COM port, it uses the standard *connection method*, and all you need to know to connect is its COM-port address:

```
from pylablib.devices import LighthousePhotonics
laser = LighthousePhotonics.SproutG("COM1")
laser.close()
```

### Laser Quantum Finesse

Laser Quantum Finesse laser implements the same basic functionality, with some small additions like controlling the shutter, reading the driving current, temperatures, etc.

The device class is `pylablib.devices.LaserQuantum.Finesse`.

Since the device shows up as a COM port, it uses the standard *connection method*, and all you need to know to connect is its COM-port address:

```
from pylablib.devices import LaserQuantum
laser = LaserQuantum.Finesse("COM1")
laser.close()
```

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

### 2.2.6 M2 Solstis laser

Solstis is a Ti:Saph laser produces by M2. It is controlled via IceBloc controller unit, which communicates with the PC via a network connection.

The main laser class is `pylablib.devices.M2.Solstis`.

#### Software requirements

The device provides a bare network interface, so no additional software is required. However, the device and the local network need to be appropriately configured, such that the PC and the laser are in the same local network and have static IPs.

In order to access some advanced features, you will need a `websocket-client` package, which is not installed with pylablib by default. You can obtain it from PyPi either separately as

```
pip install websocket-client
```

or with the expanded pylablib version

```
pip install pylablib[devio-full]
```

#### Connection

The laser is identified by its IP address (typically starting with 192.168.1, if it is on the local network) and the port:

```
>> from pylablib.devices import M2
>> laser = M2.Solstis("192.168.1.2", 34567)
>> laser.close()
```

The port is set up in the Remote interface row of the Network Settings menu of the laser web interface. There you also need to provide the correct IP address of the controlling PC and enable the remote interface; otherwise the connection will be rejected by the laser.

In addition, you can enable websocket interface option, which is used to send request directly though the device web interface. It is used for some options which are unavailable otherwise, such as enabling or disable the wavemeter connection, receiving some additional status information, and performing more robust control. Note that for proper operation the web interfaces should be opened in the browser and logged in.

#### Operation

The method names are pretty self-explanatory, and mostly correspond directly to the operations in the web interface. Note that, due to the remote interface organization, terascan requires two methods to start: first `Solstis.setup_terascan()` to specify parameters, and then `Solstis.start_terascan()` to start it.

One should note, that the device operation is not very stable, and occasionally some errors and crashes arise. These can range from failed wavelength tuning and terascan, to terascans failing in exotic ways (e.g., the remote interface suggests that the scan is in progress while the web interface reports a crash), to complete device failure requiring Ice Bloc power cycling.

The device class attempts to somewhat mitigate it by providing relatively a robust stopping method `Solstis.stop_all_operation()`, which tries to set the devices to the default idle state. It uses web interface to get a better information about the laser crashing and send additional stopping commands. It also performs additional steps to stop scans and put the laser in an operation state after a failure, such as starting quick small fine and terascans, and tuning to a nearby frequency.

### 2.2.7 M2 external mixing module (EMM)

M2 EMM allows for mixing Solstis lasers with an additional IR laser to produce higher frequency radiation. Its control principles are fairly similar to Solstis, and it is accessed through the same kind of Ice Bloc controller.

The main device class is `pylablib.devices.M2.EMM`.

#### Software requirements

Same as Solstis, the device provides a bare network interface, so no additional software is required. However, the device and the local network need to be appropriately configured, such that the PC, the EMM, and the corresponding Solstis laser are in the same local network and have static IPs.

#### Connection

The EMM is identified by its IP address (typically starting with 192.168.1, if it is on the local network) and the port:

```
>> from pylablib.devices import M2
>> emm = M2.EMM("192.168.1.2", 34567)
>> emm.close()
```

The port is set up in the Remote interface row of the Network Settings menu of the controller web interface. There you also need to provide the correct IP address of the controlling PC and enable the remote interface; otherwise the connection will be rejected by the controller.

#### Operation

The methods are organized in the same way as for the Solstis laser. Overall, the remote interface implements fewer commands, so the class provides fewer methods. Most of the commonly used methods are related to fine frequency tuning, terascan control, and status checking.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

### 2.2.8 Toptica iBeam Smart laser

Toptica iBeam Smart is a series of CW diode lasers from Toptica. The software has been tested with the standard 633nm laser.

The main device class is `pylablib.devices.Toptica.TopticaIBeam`.

#### Software requirements

The device is connected to the PC via RS232 or USB. RS232 simply requires a COM-port controller on the PC, which in most cases is a USB-to-Serial adapter. Such adapters normally come with their standard drivers. The USB version simply involves a built-in USB-to-Serial converter (e.g., a standard FTDI chip), so it also shows up as a virtual COM port. Hence, it requires relatively standard drivers, which are either included with the laser, or can be download from the [manufacturer's website](#), for example, together with the TOPAS control software.

## Connection

Since the devices are identified as virtual COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5) and, possibly, baud rate, if it is different from the standard 115200 baud:

```
>> from pylablib.devices import Toptica
>> laser1 = Toptica.TopticalBeam("COM5")
>> laser2 = Toptica.TopticalBeam(("COM10",38400)) # in case of 38400 baud connection
>> laser1.close()
>> laser2.close()
```

## Operation

### Power and output control

Usually the laser has the main power control and one or several (up to 5) output channels, which can be controlled separately. To turn the whole laser on or off, you can use *TopticalBeam.enable()*, while each channel is controlled using *TopticalBeam.enable\_channel()*. The power is set independently for each channel via *TopticalBeam.set\_channel\_power()*. The actual output power can be queried using *TopticalBeam.get\_output\_power()*.

### Detailed info

The most detailed information about the laser can be obtained using *TopticalBeam.get\_full\_data()* method. It outputs a detailed report generated by the laser, which contains most of the adjustable parameters.

### Notes and issues

Occasionally the laser communication falls into an error state, where replies are lagging behind the requests (i.e., instead of replying to the issued command, the devices replies to the previous one). This is especially likely if several commands are issued in a rapid succession. If this happens, the laser should be rebooted using *TopticalBeam.reboot()* method.

---

**Note:** General device communication concepts are described on the corresponding *page*.

---

## 2.2.9 Sirah Matisse laser

Matisse is a family of Ti:Saph and dye ring lasers produces by Sirah.

The main laser class is *pylablib.devices.Sirah.SirahMatisse*.

## Software requirements

The device requires Matisse Commander software supplied by the manufacturer. When it is installed, it shows up as a VISA resource and can be accessed without further requirements.

## Connection

The laser is identified by its VISA address, typically looking like "USB0::0x17E7::0x0102::01-01-10::INSTR":

```
>> import pylablib as pll
>> pll.list_backend_resources("visa")
('USB0::0x17E7::0x0102::01-01-10::INSTR',)
>> from pylablib.devices import Sirah
>> laser = Sirah.SirahMatisse("USB0::0x17E7::0x0102::01-01-10::INSTR")
>> laser.close()
```

Alternatively, one can use a network connection to the Matisse Commander server, if it is enabled in the Matisse Commander communication Options:

```
>> import pylablib as pll
>> from pylablib.devices import Sirah
>> laser = Sirah.SirahMatisse(("127.0.0.1", 30000)) # local server on the default port.
↪ 30000
>> laser.close()
```

## Operation

The method names are pretty self-explanatory, and mostly correspond directly to the operations in the Matisse Commander. However, only the basic tuning and scanning functions supplied by the interface are provided, and the more advanced ones like scanning BRF/etalon or interfacing with a wavemeter need to be implemented by the user based on the defined methods.

Note that depending on the specific model not all methods are available, e.g., reference cell locking is not available in TR/DR configuration.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

### 2.2.10 NKT lasers

NKT Photonics produces a variety of light sources (predominantly fiber-coupled lasers), which are frequently arranged as multi-stage modular systems. These systems consist of individual modules, which can be controlled via the main module using the common Interbus connection. The main laser class is `pylablib.devices.NKT.GenericInterbusDevice` for a generic Interbus-connected system. The code has been tested with SuperK EX-TREME white light laser equipped with SuperK SELECT tunable filter.

## Software requirements

The controllers have a built-in USB-to-RS232 adapter, which is automatically recognized as a serial port by the OS, so no additional software is required. If the device is not recognized, the drivers can be obtained from the [manufacturer website](#).

## Connection

The whole Interbus system is identified as a COM port, so it uses the standard *connection method*, and all you need to know is its COM-port address (e.g., COM5):

```
>> from pylablib.devices import NKT
>> laser = NKT.GenericInterbusDevice("COM3")
>> laser.close()
```

Within each Interbus system, there is a set of modules which can be accessed individually using their address (a number between 1 and 48). To automatically detect all available modules, you can use *GenericInterbusDevice.ib\_scan\_devices()*. Note that it typically takes relatively long time (about 25s for the full scan), so you should generally only do it when you change the Interbus arrangement by connecting or disconnecting devices or changing their addresses.

To identify, which address corresponds to which device, there are several methods. First, you can use the returned device type (also an integer between 0 and 255). You can look up the types in the SDK manual, which is freely available on the [manufacturer website](#) (you need to download SDK zip file, inside which SDK *Instruction manual.pdf* provides the necessary information). In addition, some devices either have standard addresses (e.g., Koheras BasiK K80-1 has address 10 and type 33, while SuperK EXTREME has address 15 and type 96), or allow for setting their address using switches (e.g., SuperK SELECT).

## Operation

All of the device control is done by querying and setting values of internal registers. Similar to modules themselves, registers within each module are also identified by their numerical addresses. The list of the device registers and their meaning is provided in the same SDK file as mentioned above. To access the registers, you can use *GenericInterbusDevice.ib\_get\_reg()* and *GenericInterbusDevice.ib\_set\_reg()* methods. By default these methods work with raw binary values, but you can provide the register kind (e.g., "i16" or "u8") to these methods. You can learn the kind of the registers and their precise meaning from the register files, which are available after installing the SDK. These files are located in the *Register Files* folder within the SDK, and their names correspond to the device kind in hex (e.g., the file corresponding to Koheras BasiK K80-1 will be name *21.txt*). Given this information, you can control your system. For example, the following code connects to the SuperK EXTREME module, queries its inlet temperature, sets the power setpoint and turns on the emission:

```
from pylablib.devices import NKT
laser = NKT.GenericInterbusDevice("COM3")
print(laser.ib_get_reg(15,0x11,"i16")/10) # the register is temperature in 0.1C
laser.ib_set_reg(15,0x37,600,"u16") # set power to 60% (the register is power level in
↳ 0.1%)
laser.ib_set_reg(15,0x30,3,"u8") # turn on the output (3 for on, 0 for off)
```

---

**Note:** General device communication concepts are described on the corresponding *page*.

---

### 2.2.11 Hubner Cobolt laser

Cobolt is a series of diode and diode-pumped lasers produces by Hubner Photonics. They might have several connection options (e.g., USB or direct serial RS232), but they implement the same command protocol and can be used interchangeably. The code has been tested with Cobolt 06-01 series laser using a USB connection,

The main laser class is `pylablib.devices.Hubner.Cobolt`.

#### Software requirements

When using a bare RS232 interface, any appropriate USB-to-RS232 adapter should work. When using a USB connection, one might need to install manufacturer-provided drivers. In any case, the device will be identified by the OS as a serial port.

#### Connection

Since the devices are identified as COM ports, they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Hubner
>> laser = Hubner.Cobolt("COM5")
>> laser.close()
```

#### Operation

The method names are pretty self-explanatory. The device typically lets one enable or disable the output, query key switch and interlock status, set up the operation mode (constant power/current, modulation, etc.), set up output power or current, and query some statistics (temperatures, operation hours, LED states). Note that, depending on the model, not all methods are supported.

---

**Note:** General device communication concepts are described on the corresponding *page*.

---

### 2.2.12 Tektronix oscilloscopes

Tektronix produces a large number of very widespread oscilloscopes. They have strongly overlapping, though not entirely identical, interfaces. The library has been tested with TDS2002B, TDS2004B, and DBO2014B.

The generic oscilloscope class is `pylablib.devices.Tektronix.ITektronixScope`, and the derived classes for specific devices are `pylablib.devices.Tektronix.TDS2000` of TDS2000 series and `pylablib.devices.Tektronix.DPO2000` for DPO2000/MSO2000 series.



## Software requirements

These oscilloscopes use NI VISA communication interface. Hence, it requires NI VISA Runtime, which is freely available from the [National Instruments website](#)

## Connection

The devices are identified by their VISA connection strings, which typically start with `USB0::0x0699`, e.g., `"USB0::0x0699::0x0364::C000001::INSTR"`. To get a list of all connected VISA-enabled devices, you can run `pylablib.list_backend_resources("visa")`:

```
>> import pylablib as pll
>> pll.list_backend_resources("visa")
('USB0::0x0699::0x0364::C000001::INSTR',)
>> from pylablib.devices import Tektronix
>> osc = Tektronix.TDS2000("USB0::0x0699::0x0364::C000001::INSTR")
>> osc.close()
```

## Operation

The method names are usually pretty self-explanatory. A typical operation involves setting up channels, scales, and trigger options, acquiring a waveform, and reading the result:

```
from pylablib.devices import Tektronix
osc = Tektronix.TDS2000("USB0::0x0699::0x0364::C000001::INSTR") # connect to the_
    ↳ oscilloscope
osc.enable_channel([1,2]) # enable channels
osc.set_horizontal_span(0.1) # set up horizontal and vertical spans
osc.set_vertical_span("CH1", 1)
osc.set_vertical_span("CH2", 0.1)
osc.setup_edge_trigger("CH1", 0., "dc", "rise") # set up edge trigger on channel 1 at_
    ↳ 0V threshold
osc.grab_single(wait_timeout=10.) # grab a single waveform and wait for up to 10s to_
    ↳ finish acquisition
sweeps = osc.read_multiple_sweeps([1,2]) # read out the waveforms
osc.close()
```

However, there is a couple of points to keep in mind:

- The acquisition is controlled using `grab_` methods. Generally, the most convenient way is to use `ITektronixScope.grab_single()` to acquire a single waveform (analogous to pressing a `Single` button on the oscilloscope panel). By default, this method waits until the acquisition is complete (i.e., the oscilloscope is triggered and the waveform is completely acquired) before continuing. You can also set `wait=False` to perform other operations in the meantime. The acquisition status can be queried via `ITektronixScope.is_grabbing()`, which returns `True` while the trigger is armed or while the data is recording, and `False` after the acquisition is done.
- It appears that the software trigger does not work some time (~500 ms) after the acquisition is set up. If it is invoked in `ITektronixScope.grab_single()` method by supplying `software_trigger=True`, a 300ms delay is added automatically. However, if you invoke it manually using `ITektronixScope.force_trigger()`, you should keep it in mind.
- The waveform transfer is usually performed via `ITektronixScope.read_sweep()` or `ITektronixScope.read_multiple_sweeps()` methods. Since the waveform is transferred in raw form, it requires a preamble

data (vertical and horizontal scales and offsets, data format, etc.) to translate into physical units. By default, it is acquired every time before the waveform transfer, which takes some time (up to ~200ms). Alternatively, one can acquire a preamble once and use it in subsequent reading. This method is faster, but will result in an incorrect scaling if the parameters are changed in the meantime (either remotely, or directly on the oscilloscope):

```
>> wfmpres = osc.osc.get_wfmpre([1,2])
>> %time sweeps = osc.read_multiple_sweeps([1,2])
Wall time: 2.2 s
>> %time sweeps = osc.read_multiple_sweeps([1,2], wfmpres=wfmpres)
Wall time: 450 ms
```

- The device class attempts to determine the number of channels automatically on connection, based on which requests raise device errors. However, this process takes some time, and sometimes can raise errors on not fully SCPI-compliant devices. If that is the case, it is always possible to supply the number of channels on construction:

```
>> osc = Tektronix.TDS2000("USB0::0x0699::0x0364::C000001::INSTR") # use ↵
↵ autodetection
>> osc.get_channels_number()
2
>> osc.close()
>> osc = Tektronix.TDS2000("USB0::0x0699::0x0364::C000001::INSTR", nchannels=2) # ↵
↵ specify manually
```

Keithley (currently absorbed by Tektronix) manufactures a large variety of precision electrical test and measurement equipment.

## 2.2.13 Keithley multimeters

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**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

There are different series of multimeters with somewhat different capabilities. The code has been tested with Keithley 2110 multimeter, but it should also be able to work with 2100 and 2010 series.

The main device class is `pylablib.devices.Keithley.Keithley2110`.

### Software requirements

These multimeters use NI VISA communication interface. Hence, it requires NI VISA Runtime, which is freely available from the [National Instruments website](#)

### Connection

The devices are identified by their VISA connection strings, which typically start with `USB0::0x05E6`, e.g., `"USB0::0x05E6::0x2110::0000001::INSTR"`. To get a list of all connected VISA-enabled devices, you can run `pylablib.list_backend_resources("visa")`:

```
>> import pylablib as pll
>> pll.list_backend_resources("visa")
('USB0::0x05E6::0x2110::0000001::INSTR',)
>> from pylablib.devices import Keithley
```

(continues on next page)

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```
>> meter = Keithley.Keithley2110("USB0::0x05E6::0x2110::00000001::INSTR")
>> meter.close()
```

## Operation

The operation of this multimeter is fairly straightforward, but there is a couple of points to keep in mind:

- While all measurement modes are, in principle, supported, only some of them have implemented specific parameter changing (e.g., range or resolution): voltage and current (AC and DC), resistance (2-wire and 4-wire), capacitance, frequency and period (voltage and current). These methods allow for changing of specific parameters using methods like `Keithley2110.get_vcr_function_parameters()` (get voltage, current, or resistance measurement parameters) or `Keithley2110.set_cap_function_parameters()` (set capacitance measurement parameters).
- At the same time, more universal `Keithley2110.get_configuration()` and `Keithley2110.set_configuration()` methods allow for changing basic parameters (range and resolution) for all of the applicable measurement functions (excluded are continuity, diode, and temperature modes).

Rigol manufactures a large variety of electrical test and measurement equipment, including signal generators, oscilloscopes, multimeters, power supplies, etc.

### 2.2.14 Rigol laboratory power supplies

There are different kinds of power supplies with somewhat different capabilities. The code has been tested with Rigol DP1116A.

The main device class is `pylablib.devices.Rigol.DP1116A`.

## Software requirements

These power supplies use NI VISA communication interface. Hence, it requires NI VISA Runtime, which is freely available from the [National Instruments website](#)

## Connection

The devices are identified by their VISA connection strings, which typically start with `USB0::0x1AB1`, e.g., `"USB0::0x1AB1::0x0E10::DP1A0000000000::INSTR"`. To get a list of all connected VISA-enabled devices, you can run `pylablib.list_backend_resources("visa")`:

```
>> import pylablib as pll
>> pll.list_backend_resources("visa")
('USB0::0x1AB1::0x0E10::DP1A0000000000::INSTR',)
>> from pylablib.devices import Rigol
>> supply = Rigol.DP1116A("USB0::0x1AB1::0x0E10::DP1A0000000000::INSTR")
>> supply.close()
```

## Operation

The operation of this multimeter is fairly straightforward, but there are some points to keep in mind:

- Note that the supply supports different output ranges (for DP1116A it's "16V" or "32V"), which strike different balance between output voltage and current. Other power supplies might support different output ranges, in which case the related method will raise an error or lead to communication timeout.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

### 2.2.15 NI DAQmx interface

National Instruments produces lots of different data acquisition devices, which support digital and analog input and output, both immediate and clocked (depending on the exact device). They are controlled via a very universal [NI DAQmx](#) interface. This interface is implemented in [python-nidaqmx](#) package, which provides a fairly close to original functionality, but with much more convenient Python wrappers. Pylablib implements a relatively thin wrapper around this package to present it in a way similar to the other device classes, and to simplify common tasks such as setting up voltage and counter input channels.

The main daq class is `pylablib.devices.NI.NIDAQ`. It has been tested with NI PCIe-6323, NI USB-6008, and NI USB-6363.

## Software requirements

This interface uses NI DAQmx library, which is freely available on the [National Instruments website](#). Additionally, it needs [python-nidaqmx](#) package (not to be confused with pydaqmx). It is not automatically installed with the base version of pylablib, and can be obtained from PyPi either separately as

```
pip install nidaqmx
```

or with the expanded pylablib version

```
pip install pylablib[devio-full]
```

## Connection

The devices are identified by their name, such as "Dev1". To list all of the connected devices together with their basic information, you can run `NI.list_nidaqmx_devices`:

```
>> from pylablib.devices import NI
>> NI.list_nidaqmx_devices()
[DeviceInfo(name='Dev1', model='USB-6008', serial_number='01234567')]
>> daq = NI.NIDAQ("Dev1")
>> daq.close()
```

## Operation

The typical use case involves setting up different input and output channels, starting acquisition, and acquiring some number of samples:

```
from pylablib.devices import NI
daq = NI.NIDAQ("Dev1")
daq.add_voltage_input("vin", "ai0") # add voltage input named "vin" on the terminal "ai0"
daq.add_voltage_input("vin2", "ai1", rng=(-1,1)) # add second channel with a smaller
range of +/- 1V
daq.add_digital_input("din", "port0/line0")
daq.setup_clock(100) # setup 100Hz sampling clock
trace = daq.read(100) # start acquisition, read finite number of samples, and stop it
# now do continuous acquisition + processing loop
nsamples = 0
daq.start() # start continuous acquisition
while nsamples<1000:
    sample = daq.read()
    ... process sample
    nsamples+=1
daq.stop()
```

The class provide basic methods to set up analog, digital, and counter inputs, and analog and digital outputs. All the analog and digital inputs are synchronized to the same clock, which is the default analog input sample clock (ai/SampleClock) by default. It is also possible to set up the external clock via `NIDAQ.setup_clock()` and export the sampling clock via `NIDAQ.export_clock()`. Not that not all devices support clocked digital inputs, which means that setting up digital inputs there would raise an error.

By default, the counter inputs are synchronized to the same clock, although it is possible to change that. The counter inputs have 3 modes for output values: bare counter (accumulates the number of counts), differential (number of new counts between the two sampling points), and rate (same as differential, but normalized by the sampling rate). In case of external clock, when the sampling rate is a priori unknown, it might be useful to setup a clock rate counter input to determine this clock rate via `NIDAQ.add_clock_period_input()`.

Acquisition is controlled with `NIDAQ.start()` and `NIDAQ.stop()` methods, and the readout is performed via `NIDAQ.read()`. The result of this is always a 2D numpy array, where the first index corresponds to samples and the second to channels. The order of channels can be obtained from `NIDAQ.get_input_channels()`.

The outputs can be either analog or digital. The digital outputs are always immediate, i.e., they immediately produce and hold the latest output value. The analog outputs can work in two modes: either immediate, or clocked. The mode is set up via `NIDAQ.setup_voltage_output_clock()`. In this case, it is possible to output a list of values, which produces a waveform clocked according to the specified clock: either a separate clock source (default), or the analog input clock, which makes voltage input and output synchronized.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.16 Generic AWGs

There is a large variety of Arbitrary Waveform Generators, which have very similar characteristics and communication interface.

The generic AWG class is `pylablib.devices.AWG.GenericAWG`, and the derived classes for specific devices are `pylablib.devices.AWG.Agilent33500` and `pylablib.devices.AWG.Agilent33220A` for two different Agilent AWGs, `pylablib.devices.AWG.RigolDG1000` for Rigol DG1000 series, `pylablib.devices.AWG.TektronixAFG1000` for Tektronix AFG1000 series, `pylablib.devices.AWG.InstekAFG2000` for Instek GW 2000 series, `pylablib.devices.AWG.RSInstekAFG21000` for Iso-Tech 21000 series (a clone of Instek AFG2000, but with a couple of bugs which needs to be worked around), and `pylablib.devices.AWG.InstekAFG2225` for Instek GW 2225 (slightly advanced two-channel version of Instek AFG2000).

### Software requirements

Most of these AWGs use NI VISA communication interface. Hence, they require NI VISA Runtime, which is freely available from the [National Instruments website](#). However, Instek and Iso-Tech AWGs show up as virtual COM ports, so they require no additional software.

### Connection

The devices are identified by their VISA connection strings, (e.g., "USB0::0x0699::0x0364::C000001::INSTR") or COM-port (e.g., "COM5"). To get a list of all connected VISA-enabled devices, you can run `pylablib.list_backend_resources("visa")`:

```
>> import pylablib as pll
>> pll.list_backend_resources("visa")
('USB0::0x09C4::0x0400::DG1D1502000000::INSTR',)
>> from pylablib.devices import AWG
>> dev = AWG.RigolDG1000("USB0::0x09C4::0x0400::DG1D1502000000::INSTR")
>> dev.close()
```

### Operation

The method names are usually pretty self-explanatory. A typical operation involves setting up the function, its parameters, and controlling output:

```
from pylablib.devices import AWG
dev = AWG.RigolDG1000("USB0::0x09C4::0x0400::DG1D1502000000::INSTR") # connect to the
↪ device
dev.set_function("square", 2) # set up square waveform on the second channel
dev.set_duty_cycle(20, 2)
dev.set_output_range((-1, 1), 2) # set output span from -1V to 1V
dev.enable_output(channel=2) # enable output
dev.close()
```

However, there is a couple of points to keep in mind:

- Since the same general class architecture supports both single-channel and multichannel devices, the channel argument is usually close to the end of the argument list and is not mandatory. If it is not supplied, it is chosen to be the current default channel (1 upon creation), which can be set using `GenericAWG.select_current_channel()`. Hence, in the example above we can write:

```
dev.select_current_channel(2) # now all methods assume channel 2
dev.set_function("square")
dev.set_duty_cycle(20)
dev.set_output_range((-1, 1))
dev.enable_output()
```

- Similarly, some methods can be present but not applicable to the particular AWG (e.g., burst trigger related methods, phase synchronization methods, etc.) If this is the case, they will cause an error when called.

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.17 Andor Shamrock spectrometers

In addition to cameras, Andor has a set of spectrometers primarily designed to work with and communicate through those cameras. Among these Kymera and Shamrock spectrographs have a common configuration and API.

The code is located in `pylablib.devices.Andor`, and the main device class is `pylablib.devices.Andor.ShamrockSpectrograph`. It has been tested with Kymera 328i spectrograph connected via an Andor Newton camera through I2C interface.

### Software requirements

Unfortunately, there is a large variety of different hardware setups and DLL combinations, which relate to each other in very non-obvious way. The possible adjustable parameters are

- Spectrograph connection: either via camera's I2C interface, or directly to the PC via a USB interface
- Camera AndorSDK2 DLL: on 64-bit systems it can be named `atmcd64d.dll` or `atmcd64d_legacy.dll`, and it can come from Andor Solis or Andor SDK2.
- Spectrometer DLL; on 64-bit systems it can be named `atspectrograph.dll`, `ShamrockCIF.dll`, or `ShamrockCIF64.dll`, and it might require Andor SDK2 DLLs (`atmcd64d.dll`, `atmcd64d_legacy.dll`, `atshamrock.dll`, `atshamrock64.dll`) to be located in the same folder. it can come from Andor Solis, Andor SDK2 or MicroManager plugin available on Andor/Oxford website.

As mentioned above, there are three main sources of these libraries:

- Andor Solis, which can be obtained either with the camera, or from the [website](#) upon registration.
- Andor SDK2, similarly obtained from the [website](#) (the most recent version is 2.104.30084)
- MicroManager plugin, also obtained from the [website](#) (Software section; here is the [direct link](#)).

In general, it makes sense to try different combinations of DLLs and connection methods and see what works. To specify the exact DLL sources, you use the corresponding library parameters `devices/dlls/andor_sdk2` and `devices/dlls/andor_shamrock`:

```
import pylablib as pll
pll.par["devices/dlls/andor_shamrock"] = "path/to/shamrock/dlls"
pll.par["devices/dlls/andor_sdk2"] = "path/to/sdk2/dlls"
from pylablib.devices import Andor
cam = Andor.AndorSDK2Camera()
spec = Andor.ShamrockSpectrograph()
```

Possible issues might include



- Not being able to find camera, spectrograph, or both. You can check for this by examining the outputs of `Andor.get_cameras_number_SDK2()` and `Andor.list_shamrock_spectrographs()`
- Not being able to connect both to the camera and the spectrograph simultaneously. It might be possible to connect to one of them individually, but once one connection is opened, the other one gets blocked. You can check for this directly by trying to open both the camera and the spectrograph and making sure that it works (if it does not, it will look the same as if the camera/spectrograph disappear as soon as spectrograph/camera is connected). It might be less of an issue if the spectrograph is connected directly via USB rather than via I2C through the camera.
- In some cases (especially when using libraries from the MicroManager plugin), spectrograph is identified correctly and can be connected to, but the connection is corrupted, and queries return nonsense values.
- Rarely, the spectrometer state might get corrupted, and it would stop being identified even in Andor Solis. In this case, you can try power cycling the spectrometer, camera and PC, as well as temporarily changing the spectrometer connection method (USB generally seems more stable). Just as a precaution, it is recommended to store a backup of the spectrograph EEPROM configuration, which can be done through Andor Solis. To do that, you need to go to the Hardware -> Spectrograph Setup window in the top menu, there click on the System Configuration button, and there export the EEPROM state via Save to File... button.

## Connection

The spectrographs are identified by their index, starting from zero. To list the connected spectrographs, you can run `Andor.list_shamrock_spectrographs()`:

```
>> from pylablib.devices import Andor
>> Andor.list_shamrock_spectrographs()
["KY-1234"]
>> spec = Andor.ShamrockSpectrograph(idx=0)
>> spec.close()
```

In addition, in order to acquire the spectra you need to establish the connection to the corresponding camera using *Andor cameras interface*. It is generally recommended to open the camera connection before the spectrograph to avoid software conflicts.

## Operation

The operation of these spectrographs is relatively straightforward. Note that they only allow for control of the spectrometer part of the setup (e.g., gratings, slits, filters) and for calculation of the wavelength calibration, i.e., the wavelength corresponding to each camera pixel column. In order to actually acquire and image, you would need to establish a separate camera connection and acquire images from it independently (typically in the full vertical binning, FVB, mode):

```
>> from pylablib.devices import Andor
>> cam = Andor.AndorSDK2Camera() # camera should be connected first
>> spec = Andor.ShamrockSpectrograph()
>> spec.set_wavelength(600E-9) # set 600nm center wavelength
>> spec.setup_pixels_from_camera(cam) # setup camera sensor parameters (number and size,
↳ of pixels) for wavelength calibration
>> wavelengths = spec.get_calibration() # return array of wavelength corresponding to,
↳ each pixel
>> cam.set_image_mode("fvb")
>> spectrum = cam.snap()[0] # 1D array of the corresponding spectrum intensities
```

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```
>> cam.close()
>> spec.close()
```

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.18 Miscellaneous Thorlabs devices

Thorlabs has a variety of devices implementing different serial communication protocols, mostly related to optomechanics. Their requirements and general approach are still fairly similar, so they are all collected here.

### Software requirements

Most devices provide either a bare RS232 interface, or a USB connection with a built-in USB-to-RS232 chip. In either case, they are automatically recognized as serial ports, and no additional software is required. The only exception on this page is MFF101/102 motorized flip mount, which belongs to the [Kinesis devices](#) and requires APT software.

### Connection

Most of the devices are identified as COM ports, so they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Thorlabs
>> wheel = Thorlabs.FW102("COM5")
>> wheel.close()
```

The only exception is MFF101/102, which is identified by its serial number (more details are given at the [Kinesis devices page](#)).

### Operation

#### MFF101/102 flip mount

The class is provided as `pylablib.devices.Thorlabs.MFF`. It allows for control of the flip mirror position, as well as changing its motion parameters and designations of its digital input and output.

#### FW102/212 filter wheel

The class is provided as `pylablib.devices.Thorlabs.FW`.

In addition to setting the position, it allows to adjust speed settings and turn the indicator LED off to minimize light contamination. By default, the wheel also “respects bound” between the first and the last position. Usually, when one orders a move from, e.g., position 2 to 6 on a 6-position wheel, it would go along the shortest route, i.e., position 1. If this is an ND filter wheel (e.g., FW102CNEB), this leads to momentary increase of the transmitted power by ND0.5 (about factor of 3) compared to start and stop positions. To avoid that, the class breaks this move into several shorter (no longer than 1/3 of the wheel) moves, which never cross the boundary between the first and the last position. This takes a bit longer (as it requires several consecutive moves), but is generally safer. This behavior can be turned off by setting `respect_bound=False` on class creation.

Note that older version (1.0) of the filter wheel do not support the full range of options and operate on a slightly different protocol. This leads to crashes on at least some of the methods, e.g., `FW.get_position()`. If this is the case, you can try `pylablib.devices.Thorlabs.FWv1` instead.

### MDT693/694 high-voltage source

The class is proved as `pylablib.devices.Thorlabs.MDT69xA`.

The class provides the ability to set and query the voltage on the three channels, as well as to query the total voltage range (it is set by a physical switch on the back panel, and can not be altered remotely).

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.19 OZ Optics devices

OZ Optics provides a variety of mostly fiber-optics related devices. Pylablib covers some of its fiber optomechanics solutions: polarization controller, tunable filter and variable attenuator. Their requirements and general approach are fairly similar, so they are all collected here.

### Software requirements

All the devices provide either a bare RS232 interface, or a USB connection with built-in USB-to-RS232 chip. In either case, they are automatically recognized as serial ports, and no additional software is required.

### Connection

The devices are identified as COM ports, so they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import OZOptics
>> ctl = OZOptics.EPC04("COM5")
>> ctl.close()
```

### Operation

#### EPC04 fiber polarization controller

The class is proved as `pylablib.devices.OZOptics.EPC04`. It lets the user change the 4 control voltages, switch between DC and AC (scrambling) modes, and change the AC frequency.

### DD100 fiber attenuator

The class is provided as `pylablib.devices.OZOptics.DD100`. It simply lets the user query and change the attenuation, as well as home the device. Note that homing is required once after the device power up, and it might in general sweep over the whole range of attenuations.

### TF100 fiber filter

The class is provided as `pylablib.devices.OZOptics.TF100`. It simply lets the user query and change the central wavelength, as well as home the device. Note that homing is required once after the device power up, and it might in general sweep over the whole range of wavelengths.

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

## 2.2.20 Elektro Automatik sources

Elektro Automatik manufactures a range of lab power supplies. The code has been tested with PS-2000B series controller (specifically, PS 2042-06B).

The main device class is `pylablib.devices.ElektroAutomatik.PS2000B`.

### Software requirements

The devices provide a USB connection with a built-in USB-to-RS232 chip. They are automatically recognized as serial ports by the operating system, and no additional software is required.

### Connection

Since the devices are identified as COM ports, they use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import ElektroAutomatik
>> src = ElektroAutomatik.PS2000B("COM3")
>> src.close()
```

### Operation

The operation of this gauge is fairly straightforward, but there is a couple of points to keep in mind:

- The source can operate in the manual or in the remote mode. In the manual mode the device is controlled using the front panel, but the values can still be read out. In the remote mode the outputs are controlled from the PC, and the front panel controls are disabled. Upon creation one can specify the remote mode handling for the device: either "manual" (it has to be enabled or disabled explicitly, and disabled by default) or "force" (remote mode is enabled upon connection and disabled upon disconnection).

Voltcraft produces different basic measurement and electronic devices including multimeters, oscilloscopes, signal generators, power supplies, and environment sensors.

## 2.2.21 Voltcraft multimeters

---

**Note:** Basic sensors communication concepts are described on the corresponding [page](#)

---

There are different series of multimeters with somewhat different capabilities and fairly different communication methods and protocols. There are currently two different supported protocols. The first has been designed with Voltcraft VC-7055BT multimeter, but it might also be able to work with other 7000 series multimeters such as 7060 and 7200. The second was designed with VC880, but might also work with VC650T.

The main device classes are `pylablib.devices.Voltcraft.VC7055` and `pylablib.devices.Voltcraft.VC880`.

### Software requirements

VC7055 multimeters provides a bare RS232 interface, so any appropriate USB-to-RS232 adapter should work. VC880 multimeters show up as a standard HID device and are automatically supported by Windows.

### Connection

VC7055 devices are identified as COM ports, so use the standard [connection method](#), and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Voltcraft
>> meter = Voltcraft.VC7055("COM1")
>> meter.close()
```

VC880 devices are identified either via their HID path (a fairly long and complicated string of symbols such as `\\?\hid#vid_10c4&pid_ea80#7&00000000&1&000000#{4d1e55b2-f16f-11cf-88cb-001110000030}`), and they can be identified either using this string, or an integer index (Starting from 0) which selects one of the potentially suitable devices in the system:

```
>> from pylablib.devices import Voltcraft
>> meter1 = Voltcraft.VC880() # try to connect to the first available multimeter
>> meter2 = Voltcraft.VC880(idx=1) # try to connect to the second available multimeter
>> meter1.close()
>> meter2.close()
```

### Operation

The operation of this multimeter is fairly straightforward, but there is a couple of points to keep in mind:

- The documentation from VC7055 multimeter does not always correctly reflect the communication protocol, and the device behavior is sometimes strange (e.g., it return non-ASCII symbols or strange replies to commands). The communication protocol is implemented as observed in reality, not as documented. Therefore, it is not guaranteed, that the provided code will work with related models, such as other 7000-series multimeters, or even with different revisions of the same model.
- Keep in mind that VC880 should be manually activated for PC communication by pressing PC button on the front panel, and this needs to be done every time the device is turned on. Otherwise it is detected by the OS and can be connected to, but it will not send updates or react to commands.

---

**Note:** Basic Modbus protocol concepts are described on the corresponding [page](#)

---

## 2.2.22 Lumel automation electronics

Lumel manufactures a range of automation electronics (sensors, relays, etc.), which frequently can be remotely controlled using Modbus protocol. In addition to the [generic Modbus control](#), pylablib implements RE72 temperature controller in a bit more detail. The code has been tested with RE72-122200E0 controller and generic USB to RS485 converter.

The main device classes are `pylablib.devices.Lumel.LumelRE72Controller`.

### Software requirements

Basic Lumel devices implement Modbus protocol over RS485 physical layer. If one uses a dedicated USB to RS485 controller or a USB to RS232 controller with RS232 to RS485 adapter, then it shows up as a serial port in the OS, and no additional software is required.

### Connection

Generally, you would need to know a serial port of the RS485 controller, the serial connection parameters (by default it's 9600 baud, 8 data bits, no parity bit, one stop bit) and the controller Modbus address (1 by default). For details, see [Modbus protocol description](#).

### Operation

#### RE72

There are two sets of methods implemented. The first are the generic methods for getting and setting values of internal registers: `LumelRE72Controller.get_reg()` and `LumelRE72Controller.set_reg()`. These allow full control over the device. The description of the registers is given in the user's manual (RS-485 INTERFACE section).

The second set of methods provides the basic temperature readout, as well as the setpoint control. These are implemented in two varieties, floating point and integer, according to the two kinds of registers on the device. The integer methods (ending with `i`, e.g., `LumelRE72Controller.get_measurementi()`) return integer value, whose interpretation depends on the measurement units and other parameters (e.g., for temperature this is the value in 1/10th of the current degree unit, C or F). The floating point methods return value in a more straightforward way (e.g., directly in degrees), but they do not allow for setting of the temperature setpoint.

---

**Note:** Basic Modbus protocol concepts are described on the corresponding [page](#)

---

### 2.2.23 Omron automation electronics

Omron manufactures a range of automation electronics (sensors, relays, controllers, etc.), which frequently can be remotely controlled using Modbus protocol. In addition to the *generic Modbus control*, pylablib implements E5\_C (e.g., E5GC) temperature controller in a bit more detail. The code has been tested with E5GC-QX1A6M-015 controller and generic USB to RS485 converter.

The main device classes are `pylablib.devices.Omron.OmronE5xCController`.

#### Software requirements

Basic Omron devices implement Modbus protocol over RS485 physical layer. If one uses a dedicated USB to RS485 controller or a USB to RS232 controller with RS232 to RS485 adapter, then it shows up as a serial port in the OS, and no additional software is required.

#### Connection

Generally, you would need to know a serial port of the RS485 controller, the serial connection parameters (by default it's 9600 baud, 8 data bits, even parity bit, one stop bit) and the controller Modbus address (1 by default). For details, see *Modbus protocol description*.

#### Operation

##### E5\_C

There are two sets of methods implemented. The first are the generic methods for getting and setting values of internal registers: `OmronE5xCController.get_reg()` and `OmronE5xCController.set_reg()`. These allow full control over the device. The description of the registers is given in the controller communication manual (Communications Data for Modbus section).

The second set of methods provides the basic temperature readout, as well as the setpoint control. Currently only the most basic methods for getting the current temperature (`OmronE5xCController.get_measurementi()`) and controlling the setpoint (`OmronE5xCController.get_setpointi()` and `OmronE5xCController.set_setpointi()`) are implemented

---

**Note:** General device communication concepts are described on the corresponding *page*.

---

### 2.2.24 Miscellaneous devices

There are several miscellaneous device classes, which are collected in this page. All of them implement straightforward serial communication protocol, so the software requirements and the connection approach is the same for all of them.

## Software requirements

All the devices provide either a bare RS232 interface, or a USB connection with a built-in USB-to-RS232 chip. In either way, they are automatically recognized as serial ports, and no additional software is required.

## Connection

The devices are identified as COM ports, so they use the standard *connection method*, and all you need to know is their COM-port address (e.g., COM5):

```
>> from pylablib.devices import Conrad
>> dev = Conrad.RelayBoard("COM5")
>> dev.close()
```

## Operation

### Conrad relay board

This is a board, which has several externally-controlled relays.

The class is proved as *pylablib.devices.Conrad.RelayBoard*. It simply lets the user query and set the relay states. It also in principle supports communication with several daisy-chained boards, but it has never been tested.

### Generic Arduino class

The class is proved as *pylablib.devices.Arduino.IArduinoDevice*. It implements basic serial communication; the exact command protocol depends on the particular Arduino software written and uploaded by the user.

The main difference from directly using a serial backend is in handling of DTR line, which signal reset to the Arduino board. Unlike the standard backend, connection will not restart the board; instead, there is an explicit *IArduinoDevice.reset\_board()* which pulses the DTR line to reset the board.

## 2.2.25 Generic Windows devices

There is some support for generic Windows drivers for some devices.

### Joysticks

Basic support for Windows-compatible joysticks / gamepads using WinMM. Since the driver only supports polling, the events (button/axis presses) are emulated using a separate polling loop. The main device class is *pylablib.devices.Windows.Joystick*. Since this library is a standard part of Windows, no additional software is required, apart from potential joystick drivers.

The code supports polling the joystick state (button and axes) as well as querying events:

```
>> from pylablib.devices import Windows
>> Windows.list_joysticks()
{0: TDeviceInfo(name='Microsoft PC-joystick driver', id=(121, 17), nbuttons=10, naxes=2)}
>> j=Windows.Joystick()
>> j.get_buttons()
```

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```
[False, False, False, False, False, False, False, False, False, False]
>> j.start() # start polling loop in a separate thread
>> j.get_events() # get the recent events (since the last get_events call)
TJoystickEvent(kind='axis', index=0, old=0, new=-1, timestamp=1000000000.000),
TJoystickEvent(kind='axis', index=0, old=-1, new=0, timestamp=1000000001.000)]
>> j.stop() # stop the polling loop when done
```

---

**Note:** General device communication concepts are described on the corresponding [page](#).

---

## 2.2.26 Generic protocols

There exist generic mid-level communication protocols built on top of the existing communication channels. These are not specific to any particular device, but simply provide a level of abstraction to implement specific devices later.

### Modbus

This is one of the standard industrial communication protocols. It has several different implementations depending on the underlying protocol (UART, TCP). Currently only Modbus RTU (binary protocol over UART) is supported.

The code is located in `pylablib.devices.Modbus`, and the main camera class is `pylablib.devices.Modbus.GenericModbusRTUDevice`.

### Software requirements

The requirements depend on the underlying transfer layer. Most common is the RS485 physical layer, where one normally uses either a dedicated USB to RS485 controller, or a USB to RS232 controller with RS232 to RS485 adapter. In this case, the RS485 controller shows up as a serial port in the OS, and no additional software is required.

### Connection

To successfully communicate with a device, several pieces of information are needed. First, one needs to know the serial port of the RS485 controller (e.g., "COM1" or "dev/ttyUSB0"). Next are the serial port parameters, such as the baud rate, number of data bits, parity bits, and stop bits (the most common is 9600 baud with 8N1 format, i.e., 8 data bits, one parity bit, 1 stop bit). Finally, since several Modbus devices can be connected to the same controller, one needs to know the specific device address, which is an integer between 1 and 247. Both the serial port parameters and the device address are set at the device or specified in its documentation:

```
>> from pylablib.devices import modbus
>> dev = modbus.GenericModbusRTUDevice(("COM3", 19200), daddr=5) # 19200 baud serial_
↪interface, default device address 5
>> dev.close()
```

---

**Note:** Serial ports are exclusive OS resources, which means that only one instance of `modbus.GenericModbusRTUDevice` can be opened at the same port, even if several devices are connected to the same RS485 controller. One can choose which device is addressed either by using `daddr` parameter in the methods, or by using `GenericModbusRTUDevice.mb_set_default_address()` method.

---



## Operation

The code implements the most basic Modbus methods for setting and reading coils, discrete inputs, and registers. All relevant methods are prefixed with `mb_`, e.g., `GenericModbusRTUDevice.mb_read_holding_registers()` or `GenericModbusRTUDevice.mb_write_single_coil()`. In addition, it implements a basic device scanning method, which sends the same command to all possible addresses and notes which of them reply.

## 2.3 Data processing

### 2.3.1 Fitting

Class `fitting.Fitter` is a user-friendly wrapper around `scipy.optimize.least_squares()` routine. Dealing with fitting is made more convenient in a couple of ways:

- It is easy to specify the x-parameter name (in the case it is not the first parameter), or specify multiple x-parameters;
- All of the fit and fixed parameters are specified by name; it is easy to switch between any parameter being fit or fixed;
- The wrapper automatically handles complex parameters (split into real and imaginary parts), numpy arrays, lists, or tuples (including nested structures);
- The final parameters (fit and fixed) are returned in a single dictionary indexed by their names;
- The wrapper also returns the fit function with all of the parameters bound to the final fit and fixed values;
- The fit function result is flattened during fitting, so it works for functions returning multi-dimensional (for example, 2D) arrays.

### Examples

Fitting a Lorentzian:

```
def lorentzian(frequency, position=0., width=1., height=1.):
    return height/(1.+4.*(frequency-position)**2/width**2)

## creating the fitter
# fit_parameters dictionary specifies the initial guess
fit_par = {"position":0.5, "height":1.}
fitter = pll.Fitter(lorentzian, xarg_name="frequency", fit_parameters=fit_par)
# additional fit parameter is supplied during the call
fit_par, fit_func = fitter.fit(xdata, ydata, fit_parameters={"width":1.0})
plot(xdata, ydata) # plot the experimental data
plot(xdata, fit_func(xdata)) # plot fit result
```

Fitting a sum of complex Lorentzians with the same width:

```
def lorentzian_sum(frequency, positions, width, amplitudes):
    # list of complex lorentzians
    # positions and amplitudes are lists, one per peak
    lorentzians = [a/(1.+2j*(frequency-p)/width) for (a,p) in zip (amplitudes,positions)]
    return np.sum(lorentzians, axis=0)
```

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```

## creating the fitter
# fit_parameters dictionary specifies the initial guess
# (complex initial guess for the "amplitude" parameter hints that this parameter is_
↳ complex)
fit_par = {"positions": [0., 0.5, 1.], "amplitudes": [1.+0.j]*3}
fitter = pll.Fitter(lorentzian_sum, xarg_name="frequency", fit_parameters=fit_par)
# fixed parameter is supplied during the call (could have also been supplied on Fitter_
↳ initialization)
fit_par, fit_func = fitter.fit(xdata, ydata, fixed_parameters = {"width": 0.3})
plot(xdata, ydata.real) # plot the experimental data
plot(xdata, fit_func(xdata).real) # plot fit result

```

Fitting 2D Gaussian and getting the parameter estimation errors:

```

def gaussian(x, y, pos, width, height):
    return np.exp( -((x-pos[0])**2+(y-pos[1])**2)/(2*width**2) )*height

## creating the fitter
# fit_parameters dictionary specifies the initial guess
fit_par = {"pos": (100, 100), "width": 10., "height": 5.}
fitter = pll.Fitter(gaussian, xarg_name=["x", "y"], fit_parameters=fit_par)
xs, ys = np.meshgrid(np.arange(img.shape[0]), np.arange(img.shape[1]), indexing="ij") #_
↳ building x and y coordinates for the image
# fit_stderr is a dictionary containing the fit error for the corresponding parameters
fit_par, fit_func, fit_stderr = fitter.fit([xs, ys], img, return_stderr=True)
imshow(fit_func(xs, ys)) # plot fit result

```

The full module documentation is given at [pylablib.core.dataproc.fitting](#).

## 2.3.2 Filtering and decimation

There are several functions present for filtering the data to smooth it or reduce its size. Most of them are thin wrappers around standard numpy or scipy method, but they provide more universal interface which work both with numpy arrays and pandas DataFrames:

- First are the decimation functions: `filters.decimate()` (and its special case `filters.binning_average()`), `filters.decimate_full()` and `filters.decimate_datasets()`. The first one splits the supplied trace into consecutive segments of  $n$  points and compresses them into a single value using the supplied method (e.g., "mean" will average them together, which is used for `filters.binning_average()`). The second one completely decimates the dataset along the given axis (which is essentially identical to using the standard numpy methods such as `np.mean` or `np.max`). The last one decimates several datasets together, which is similar to combining them into a large  $(n+1)D$  array and fully decimating along the given axis:

```

>> trace = np.arange(10)
>> pll.binning_average(trace, 3) # average every block of 3 points to a single_
↳ value
array([1., 4., 7.])
>> pll.decimate(trace, 3, dec="max")
array([2, 5, 8])
>> pll.decimate_full(trace, "mean") # same as np.mean(trace)
4.5
>> trace2 = np.arange(10)**2

```

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```
>> pll.decimate_datasets([trace, trace2], "sum") # same as np.sum([trace, trace2],
↪axis=0)
array([ 0,  2,  6, 12, 20, 30, 42, 56, 72, 90])
```

- Sliding decimation methods `filters.sliding_average()`, `filters.median_filter()` and `filters.sliding_filter()` are related, but use a sliding window of  $n$  points instead of complete decimation of  $n$  points together. They only work for 1D traces or 2D multi-column datasets. Note that `filters.sliding_filter()` is implemented through a simple Python loop, so it is fairly inefficient:

```
>> trace = np.arange(10)
>> pll.sliding_average(trace, 4) # average points in 4-point window (by default,
↪use "reflect" boundary conditions)
array([0.75, 1.5 , 2.5 , 3.5 , 4.5 , 5.5 , 6.5 , 7.5 , 8.25, 8.5 ])
>> pll.sliding_filter(trace, 4, "max") # find maximum of points in 4-point window
array([2, 3, 4, 5, 6, 7, 8, 9, 9, 9])
```

- Next are convolution filters which operate by convolving the trace with a given kernel function. These involve `filters.gaussian_filter()` (and `filters.gaussian_filter_nd()`, which is simply a wrapper around `scipy.ndimage.gaussian_filter()`), and a more generic `filters.convolution_filter()`. Related are infinite impulse response (IIR) filter `filters.low_pass_filter()` and `filters.high_pass_filter()`, which mimic standard single-pole low-pass and high-pass filters. In principle, they can be modeled as a convolution with an exponential decay, but the implementation using the recursive filters is more efficient for large widths.
- Finally, there are Fourier filters, which Fourier-transform the trace, scale the transform values, and transform it back to the real domain. These involve the main function `filters.fourier_filter()`, which takes a generic frequency response function, as well as two specific response function generators `filters.fourier_filter_bandpass()` and `filters.fourier_filter_bandstop()`, both generating hard frequency cutoff filters.
- In addition to “post-processing” filters described above, there are also “real-time” filters which serve to filter data as it is acquired, e.g., to filter out temporary noise or spikes. There are two filters of this kind: `filters.RunningDecimationFilter` and `filters.RunningDebounceFilter`. They are implemented as classes, and both have methods to add a new datapoint, to get the current filter value, and to reset the filter.

### 2.3.3 Fourier transform

There is a couple of methods to work with Fourier transform. They are built around `numpy.fft.fft()`, but allow more convenient normalization (e.g., in units of power spectral density), and work better with pandas DataFrames. They also have an option to automatically trim the trace length to the nearest “good” size, which is a product of small primes. This can have fairly strong (up to a factor of several) effect on the transform runtime, while typically trimming off less than 1% of the data.

The main methods are `fourier.fourier_transform()` for the direct transform, `fourier.inverse_fourier_transform()` for the inverse transform, and `fourier.power_spectral_density()` for the power spectral density:

```
>> x = np.random.normal(size=10**5) # normal distribution centered at 0 with a width of 1
↪1
>> PSD = pll.power_spectral_density(x, dt=1E-3) # by default, use density normalization;
↪assume time step of 1ms
>> df = PSD[1,0] - PSD[0,0]
>> df # total span is 1kHz with 10**5 points, resulting in 0.01Hz step
```

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```
0.01
>> np.sum(PSD[:,1]) * df # integrated PSD is equal to the original trace RMS squared,
↳ which is about 1 for the normal distribution
1.005262206692361
>> np.mean(x**2)
1.005262206692361
```

## 2.3.4 Feature detection

There are several methods for simple feature detection:

- The peak detection, which is usually achieved by the combination of `feature.multi_scale_peakdet()` and `feature.find_peaks_cutoff()`. The first applies difference-of-Lorentzians or difference-of-Gaussians filter, which detects peaks of a particular width. The second finds peaks using a cutoff.
- Another way to find peaks is using `feature.find_local_extrema()`, which finds local minima or maxima in a sliding window of a given width.
- Switching between two states with a noisy trace can be detected using `feature.latching_trigger()`. It implements a more robust approach to find when the trace is above/below threshold by considering two thresholds: a higher “on” thresholds and a lower “off” threshold. It makes the on/off state “latch” to its current value and is robust to small trace fluctuations around the threshold, which would lead to rapid on/off switches in a single-threshold scheme.

## 2.3.5 Miscellaneous utilities

Additionally, there is a variety of small functions to simplify some data analyses and transforms:

- Checking trace properties: `dataproc.utils.is_ascending()`, `dataproc.utils.is_descending()`, `dataproc.utils.is_ordered()`, `dataproc.utils.is_linear()`.
- Sorting by a given column: `dataproc.utils.sort_by()`; work both on pandas and numpy arrays
- Filtering: `dataproc.utils.filter_by()` and `dataproc.utils.unique_slices()` (a simple analog of pandas `pandas.DataFrame.groupby()`, which works on numpy arrays)
- Binary search (both in ordered and unordered 1D arrays): `dataproc.utils.find_closest_arg()`, `dataproc.utils.find_closest_value()`, and `dataproc.utils.get_range_indices()`.
- Traces step analysis and unwrapping: `dataproc.utils.find_discrete_step()` tries to find a single number which divides all values within a reasonable precision, and `dataproc.utils.unwrap_mod_data()` “unwraps” modulo data (e.g., phase, which is defined mod  $2\pi$ ) provided that the steps between two consecutive points are less than  $1/2$  of the module.
- Cutting the trace to the given range, or cutting out a given range: `dataproc.utils.cut_to_range()` and `dataproc.utils.cut_out_regions()`.
- Converting between 2-column “XY” and complex representations: `dataproc.utils.xy2c()` and `dataproc.utils.c2xy()`
- Scalar numerical utilities: `utils.numerical.limit_to_range()` (limit a value to lie in a given range, including option for no limits in one or both directions), `utils.numerical.gcd()` and `utils.numerical.gcd_approx()` (greatest common divisor or its approximate version for non-integer values)

## 2.4 Data storage

Complex data storage in pylablib centers around 2 main components: the multi-level dictionary for representing hierarchical data within the code, and file IO to (among other things) load and store it in a human-readable format.

### 2.4.1 Multi-level dictionary

`dictionary.Dictionary` is an expansion of the standard `dict` class which supports tree structures (nested dictionaries). The extensions include:

- handling multi-level paths and nested dictionaries, with several different indexing methods
- iteration over the immediate branches, or over the whole tree structure
- some additional methods: mapping, filtering, finding difference between two dictionaries
- combined with `pylablib.core.fileio` allows to save and load the content in a human-readable format.

Creating and indexing:

```
>>> d = pll.Dictionary()
>>> d['d/0/x'] = 5
>>> d
Dictionary('d/0/x': 5)
>>> d['d/0/x'] # string path indexing
5
>>> d['d']['0']['x'] # nested indexing
5
>>> d['d','0','x'] # multi-level path indexing
5
>>> d['d',0,'x'] # all path elements are converted into strings
5
>>> d['d/0']['x'] # indexing styles can be freely mixed
5
>>> d['d','0/x']
5
>>> b = d['d'] # indexing a branch yields another Dictionary object
>>> b
Dictionary('0/x': 5)
>>> b['0/x'] = 10 # the branch shares the data with the main dictionary
>>> d
Dictionary('d/0/x': 10)
```

A dictionary can be build from a Python `dict`, which automatically normalizes paths and nested dictionaries:

```
>>> d = pll.Dictionary({ 'a':1, 'b/i':2, 'c':{'i':3, 'ii':4}, 'd/0/x':5 })
>>> d
Dictionary('b/i': 2
'c/i': 3
'c/ii': 4
'd/0/x': 5
'a': 1)
```

**Note:** There are several limitations on the dictionary structure (mostly they involve possible paths and keys):

- As mentioned above, the keys are converted into strings to get the path; therefore, different Python object can merge together (e.g., number 0 and string literal '0'). This also discourages use of some of the objects with “underdefined” (implementation dependent) representations, for example, floating point numbers.
- Since the '/' symbol is used to split different path entries, it can't be used inside a single-level key. It is possible to re-define this symbol on dictionary creation; however, it might lead to compatibility issues.
- Empty keys are not allowed. When building a path, they are automatically dropped, so 'a/b', 'a/b/', 'a///b/' all correspond to the same path.
- One path can either correspond to a branch node, or a leaf node. In other words, one path can't be a prefix of other paths and also contain data: structures like `p11.Dictionary({'a':1, 'a/b':2})` are not allowed. To get around this, one can define a specific “data key” not used anywhere else, and store data in a node under that key (e.g., with the data key '#' the example before turns into a valid structure `p11.Dictionary({'a/#':1, 'a/b/#':2})`).

Thus, it is generally recommended to only use strings or non-negative integers as keys, and apply the same restrictions to them as to the Python variable names (with the addition of names starting with a digit).

---

## 2.4.2 File IO

`pylablib.core.fileio` contains several function for saving and loading data into different kinds of files: binary (`loadfile.load_bin()` and `savefile.save_bin()`), CSV (`loadfile.load_csv()` and `savefile.save_csv()`), or dictionary (`loadfile.load_dict()` and `savefile.save_dict()`).

### Binary files

The first (binary files) closely corresponds to numpy `fromfile`. In addition, it also allows automatic conversion into pandas arrays, setting column names, and skipping some number of bytes from the start:

```
>> table = np.arange(6).reshape((3,2))
>> p11.save_bin(table, "table.dat", dtype="<f8")
>> p11.load_bin("table.dat", columns=["Column1", "Column2"], dtype="<f8")
  Column1  Column2
0      0.0      1.0
1      2.0      3.0
2      4.0      5.0
```

Furthermore, there is an option to save the binary data with a preamble dictionary file, which describes its structure (columns, dtype, etc.) This way, one does not have specify these parameter in the loading code:

```
>> table = pd.DataFrame({"C1":range(3),"C2":range(3)**2/3})
>> table
   C1      C2
0  0  0.000000
1  1  0.333333
2  2  1.333333
>> p11.save_bin_desc(table, "table.dat")
>> p11.load_bin_desc("table.dat")
   C1      C2
0  0.0  0.000000
1  1.0  0.333333
2  2.0  1.333333
```

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```
>> np.fromfile("table_data.bin", "<f8").reshape((3, 2)) # the data is still stored in
↳ the regular binary format
array([[0., 0.],
       [1., 0.33333333],
       [2., 1.33333333]])
```

Note that only homogeneous data (i.e., all columns having the same type) is currently supported. That's why the first column got converted from integers into reals.

## CSV files

The functionality of the second one mimics pandas `read_csv`, but offers a bit more flexibility with more complicated values in columns, such as tuples or binary strings:

```
>> table = pd.DataFrame({ "C1":np.arange(3), "C2":[(i**2,i**3) for i in range(3)] })
>> table # the second columns contains tuples
   C1    C2
0    0  (0, 0)
1    1  (1, 1)
2    2  (4, 8)
>> pll.save_csv(table, "table.csv")
>> pll.load_csv("table.csv", dtype="generic") # need to specify generic values type,
↳ which handle complicated cases, but is somewhat slower
   C1    C2
0    0  (0, 0)
1    1  (1, 1)
2    2  (4, 8)
```

In addition, its default settings are a bit different: the column separator is a whitespace, the column names are contained in the comment string (which removes occasional ambiguity), and the creation date string is appended by default. Hence, the content of the file created above is

```
# C1      C2
0    (0, 0)
1    (1, 1)
2    (4, 8)

# Saved on 2021/01/01 12:00:00
```

Note that currently it operates only with simple flat tables and does not support advanced pandas features such as index or multi-index. If these are required, you can use `savefile.save_csv_desc()` and `loadfile.load_csv_desc()`. Similarly to `savefile.save_bin_desc()` and `loadfile.load_bin_desc()`, it saves a dictionary containing additional description; however, the table is inlined by default, so only one file is generated:

```
>> table = pd.DataFrame({ "C1":np.arange(3), "C2":[(i**2,i**3) for i in range(3)] },
↳ index=np.arange(3)+10)
>> table # non-trivial index column
   C1    C2
10   0  (0, 0)
11   1  (1, 1)
12   2  (4, 8)
>> pll.save_csv(table, "table.csv")
```

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```
>> pll.load_csv("table.csv", dtype="generic") # index is lost
      C1      C2
0      0  (0, 0)
1      1  (1, 1)
2      2  (4, 8)
>> pll.save_csv_desc(table, "table.dat")
>> pll.load_csv_desc("table.dat") # index is preserved (also note that here dtype is
  ↳ "generic" by default)
      C1      C2
10     0  (0, 0)
11     1  (1, 1)
12     2  (4, 8)
```

## Dictionary files

Finally, dictionary saving and loading operates with *dictionary* objects. It is generally useful to load or save various heterogeneous settings or parameters, such as device parameters, data processing parameters, and GUI or device state. It supports most basic Python data types as values: standard scalar types (integers, reals, complex numbers, strings, booleans, None), containers (tuples, lists, dictionaries, sets, including nested ones), binary and raw string representation (e.g., `b"\x00"` or `r"\m\n\o"`), short numpy arrays (represented as, e.g., `"array([1, 2, 3])"`), and inline tables (which are interpreted as pandas table by default). The only common data type not included is named tuples; they get automatically converted to regular tuples on saving.

The dictionary files have the `key value` line formats and typically use full paths (as opposed to, say, XML hierarchy), which makes them easier to inspect and parse without pylablib. For example, the dictionary from the previous section will be saved as

```
b/i 2
c/i 3
c/ii 4
d/0/x 5
a 1
```

With more complicated data types, it might look more like

```
process/points array([1., 2., 3.])
process/default/frequency 10+2.j
# Lines starting with # are treated as comments
plot/position [(0,0), (1,1), (2,3)]
plot/label r"$\nu_0$"
# Keys do not have to be in any particular order
process/default/amplitude 5.
```

which results in a dictionary

```
Dictionary({'plot/label': '$\nu_0$'
'plot/position': [(0, 0), (1, 1), (2, 3)]
'process/default/amplitude': 5.0
'process/default/frequency': (10+2j)
'process/points': [1. 2. 3.]})
```

The format also supports hierarchy using `//branch` to mark a start of sub-branch and `///` to mark its end. For example, the dictionary above can be also saved as



```
//process
# indentation is not required, but helps to see the structure
points array([1., 2., 3.])
default/frequency 10+2.j
default/amplitude 5.
///

//plot
position [(0,0), (1,1), (2,3)]
label r"$\nu_0$"
///
```

Finally, it is possible to specify inline tables using special comment lines. For example,

```
# The key without the value marks the path to the table within the dictionary
data/table
## Begin table
1 1.j
2 4.j
3 9.j
## End table
```

produces a dictionary containing pandas DataFrame:

```
Dictionary('data/table':
  0      1
0 1  0.000000+1.000000j
1 2  0.000000+4.000000j
2 3  0.000000+9.000000j )
```

## 2.5 Various utilities

### 2.5.1 File system

There is a number of methods which are minor expansions of the built-in file utilities:

- Accessing and changing file times: `utils.files.get_file_creation_time()`, `utils.files.get_file_modification_time()`, `utils.files.touch()` (update the modification date).
- Generating new file names (e.g., for storing a new dataset): `utils.files.generate_indexed_filename()` and `utils.files.generate_prefixed_filename()`.
- Some path analysis methods: `utils.files.fullsplit()`, `utils.files.normalize_path()`, `utils.files.paths_equal()`, `utils.files.relative_path()`; a lot of these have also been implemented in `pathlib` module, and are kept for backwards compatibility.
- Checking if a string is a valid path: `utils.files.is_path_valid()`.
- File copying and moving, which also creates containing folders if necessary: `utils.files.copy_file()`, `utils.files.move_file()`.
- Folder creation and cleaning: `utils.files.ensure_dir()`, `utils.files.remove_dir()`, `utils.files.remove_dir_if_empty()`, `utils.files.clean_dir()`.

- Analyzing folder content: `utils.files.list_dir()`, `utils.files.list_dir_recursive()`, `utils.files.dir_empty()`, `utils.files.walk_dir()`. Compared to the built-in methods, allows for more complicated (e.g., regex) filters for listed files and folders, as well as for visited folders.
- Copying, moving, and comparing folders: `utils.files.copy_dir()`, `utils.files.move_dir()`, `utils.files.cmp_dirs()`; like methods above, allows for regex filters for files and folders.
- Retrying versions of most of the above methods: e.g., `utils.files.retry_move()` or `utils.files.retry_clean_dir()`. These functions try to copy/move/remove files or folders several times if errors arise, in case the files or folders are only temporarily blocked. Useful when, e.g., using network shares or some software which makes files or folders unavailable for a short period of time.
- Wrapping methods for working with zip files: `utils.files.zip_folder()`, `utils.files.zip_file()`, `utils.files.zip_multiple_files()`, `utils.files.unzip_folder()`, `utils.files.unzip_file()`.

## 2.5.2 Network

There is a simple wrapper class `utils.net.ClientSocket`, which simplifies some operations with the built-in `socket` module. In addition, it also implements a couple of higher-level ways to send the data: either fixed length (as in the usual socket), with the length prepended (in case the total length is initially unknown at the receiving end), or using a delimiter to mark the end of the message.

In addition, there are several methods for gaining local or remote host information (`utils.net.get_local_addr()`, `utils.net.get_all_local_addr()`, `utils.net.get_local_hostname()`, `utils.net.get_all_remote_addr()`, `utils.net.get_remote_hostname()`), receiving JSON-formatted values (`utils.net.recv_JSON()`), and listening on a given port (`utils.net.listen()`).

## 2.5.3 Strings

There are several string manipulation functions present:

- Powerful to/from string conversion. The main function are `utils.string.to_string()` and `utils.string.from_string()`, which can convert a large variety of values: simple scalar values (numbers, strings, booleans, None), containers (lists, tuples, sets, dictionaries), escaped and byte strings (e.g., `b"\x00"`), complex types such as numpy arrays (represented as, e.g., `"array([0, 1, 2, 3, 4])"`). The latter version requires setting `use_classes=True` in `utils.string.to_string()`, which is not enabled by default to make the results more compatible with other parsers:

```
>> pll.to_string(np.arange(5)) # by default, use the standard str method, which_
↳ makes array look like a list
'[0, 1, 2, 3, 4]'
>> pll.from_string('[0, 1, 2, 3, 4]') # gets converted back into a list
[0, 1, 2, 3, 4]
>> pll.to_string(np.arange(5), use_classes=True) # use representation class
'array([0, 1, 2, 3, 4])'
>> pll.from_string('array([0, 1, 2, 3, 4])') # get converted back into an array
array([0, 1, 2, 3, 4])
```

More complex data classes can be added using `utils.string.add_conversion_class()` and `utils.string.add_namedtuple_class()`:

```
>> NamedTuple = collections.namedtuple("NamedTuple", ["field1", "field2"])
>> nt = NamedTuple(1,2)
>> nt
```

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(continued from previous page)

```

NamedTuple(field1=1, field2=2)
>> pll.to_string(nt, use_classes=True) # class is not registered, so use the
↳ default tuple representation
'(1, 2)'
>> pll.add_namedtuple_class(NamedTuple)
>> pll.to_string(nt, use_classes=True) # now the name marker is added
'NamedTuple(1, 2)'
>> pll.from_string('NamedTuple(1, 2)')
NamedTuple(field1=1, field2=2)
>> DifferentNamedTuple = collections.namedtuple("DifferentNamedTuple", ["field1",
↳ "field2"])
>> pll.from_string('DifferentNamedTuple(1, 2)') # note that if the class is not
↳ registered, it can't be parsed, so the string is returned back
'DifferentNamedTuple(1, 2)'

```

Furthermore, there is a couple of auxiliary string functions to parse more complicated situations: `utils.string.escape_string()` and `utils.string.unescape_string()` for escaping and unescaping string with potentially confusing or unprintable characters (e.g., quotation marks, spaces, new lines); `utils.string.from_string_partial()`, `utils.string.from_row_string()`, `utils.string.extract_escaped_string()` to determine and extract the first value in a string which potentially has several values.

- Comparing and searching string: `utils.string.string_equal()` (compare string using different rules such as case sensitivity), `utils.string.find_list_string()`, `utils.string.find_dict_string()` (find string in a list or a dictionary using different comparison rules).
- Filtering strings: `utils.string.get_string_filter()`, `utils.string.sfglob()`, and `utils.string.sfreqex()`. Creates filter functions which may include or exclude certain string patterns; these filter functions can be later used in, e.g., file-related methods such as `utils.files.list_dir()`.

## 2.5.4 Misc utilities

A variety of small useful methods and classes:

- Dictionary manipulation functions: `utils.general.any_item()` (get a random dict key-value pair), `utils.general.merge_dicts()` (merge several dictionaries together), `utils.general.filter_dict()` (filter dictionary according to key or value), `utils.general.map_dict_keys()`, `utils.general.map_dict_values()`, `utils.general.to_dict()` (convert a dict or a list of pairs into a dictionary, using a default value for a non-pair list elements), `utils.general.invert_dict()` (turn keys into values and vice versa).
- List manipulation functions: `utils.general.flatten_list()` (flatten a nested list structure), `utils.general.partition_list()` (split a list into two lists according to a predicate), `utils.general.split_in_groups()` (split list into several groups according to a key function), `utils.general.sort_set_by_list()` (convert set into a list, whose values are sorted according to a second supplied list), `utils.general.compare_lists()` (compare two lists and return their intersection and differences).
- `utils.general.DummyResource`: a “dummy” resource class, which can be used in a with block but does nothing; can be used to, e.g., replace multi-threading resources such as locks to turn them off.
- Unique ID generators: `utils.general.UIDGenerator` and `utils.general.NamedUIDGenerator`, which generate unique names (based on a counter), with a thread-safe option (useful to create, e.g., unique data markers).
- Timekeeping: `utils.general.Countdown` for single shot and `utils.general.Timer` for repeating tasks.

Simplifies dealing with operation timeouts: checking how much time is left (including options for infinite timeout), checking if timeout is passed, resetting, etc.

- Script restarting via `utils.general.restart()` (thread-controller style applications can also use `thread.controller.restart_app()` for a more managed restart).
- `utils.general.StreamFileLogger`, which can be set up to log all outputs into a stream (e.g., `stdout`):

```
from pylablib import StreamFileLogger
import sys
sys.stderr = StreamLogger("logerr.txt", sys.stderr) # replace stderr stream with a
↳ logged version
# perform some tasks ...
sys.stderr = sys.stderr.stream # revert back, if necessary
```

With the code above, all output to `stderr` will be logged into `logerr.txt` to be analyzed later. It can also be set with `autoflush=True` to automatically flush the printed text, which helps with identifying crushing bugs, and it can be supplied with a lock to help separate printouts from different threads.

## 2.6 Change log

This is a list of changes between each version.

### 2.6.1 Version 1.x

Transitioning from version 0.x to version 1.x saw lots of interface changes which break backward compatibility. The previous version of the library can be either obtained on PyPi using `pip install "pylablib<1"`, or by using `legacy` module. Hence, instead of

```
import pylablib as pll
from pylablib.aux_libs.devices import Lakeshore
```

you can write

```
import pylablib.legacy as pll
from pylablib.legacy.aux_libs.devices import Lakeshore
```

### 1.4.3

- Devices
  - Added multiple devices:
    - \* Agilent XGS600 pressure gauge controller
    - \* Hubner Cobolt lasers (tested with Cobolt MLD 06-01 laser)
    - \* Omron E5\_C temperature controllers (tested with E5GC-QX1A6M-015 controller)
    - \* Thorlabs Kinesis Piezo controllers (tested with KPZ101)
  - Extended device support:
    - \* Multi-axis Trinamic TMCN controllers (tested with TMCN6110)
    - \* Matisse Commander server support for Sirah Matisse lasers

- \* Added trigger mode selection for uc480/uEye cameras
- Bug fixes and improved support of specific models:
  - \* Thorlabs Scientific Cameras monochrome bug
  - \* Fixed minor Thorlabs Kinesis enumeration bugs and KIM101 channel selection bug

- **Minor additional functions and bugfixes**

- Fixed module versioning bug which prevented the use of PyInstaller
- GUI additions: button-selector widgets (alternative to combo box), tab hiding, widget tags for finer GUI control

## 1.4.2

- **Devices**
  - Added multiple devices:
    - \* Andor Shamrock spectrographs
    - \* ElektorAutomatick PS2000B power supply
    - \* Keithley 2110 multimeter
    - \* Lumel RE72 temperature controller (via Modbus RTU protocol)
    - \* M2 Solstis EMM (external mixing module)
    - \* Mightex S-Series cameras
    - \* Generic NKT lasers Interbus protocol support (tested with NKT SuperK with Select spectral filter)
    - \* Generic Modbus RTU protocol
    - \* PhysikInstrumente E-515 piezo controller
    - \* Rigol DP1116A power supply
    - \* SmarAct MCS2 stage controller
    - \* Standa 8SMC5 motion controller
    - \* Thorlabs PM160 power meter
    - \* Voltcraft VC-7055BT multimeter
  - Extended device support:
    - \* Thorlabs Scientific Cameras (Zelux, Kiralux) color mode
    - \* Thorlabs APT/Kinesis motor controllers
    - \* Trinamic TMC110 homing
  - Added HID device communication backend
  - Switched some camera code to Cython to support higher frame rates.
  - Multiple bug fixes and improved support of specific models:
    - \* Selection of RTS cycling for Arduino boards (better support for newer boards such as Leonardo)
    - \* Support for SiliconSoftware microEnable 5 (Basler microEnable 5 marathon)
    - \* Improved Sirah Matisse tuning support for frequency tuning and stitched scans based on HighFinesse wavemeters feedback.

- Switched to Cython code in several places for minor plotting speedups.
- **Minor additional functions**
  - Added time tracker class for simple profiling
  - Added CRC calculation methods

#### 1.4.1

- Devices
  - Added Basler pylon-compatible cameras, BitFlow frame grabbers, AlliedVision Bonito cameras, Thorlabs Elliptec stages, PI-E516 piezo controller, and Sirah Matisse laser.
  - Minor additions to Cryocon temperature controller, Cryomagnetics LM510 level meters, and NI DAQmx DAQs. Improved performance of PCO cameras at high frame rates.
  - Multiple minor bug fixes and improved support of specific models.
- Added encoding argument to file loading.
- Improved color images support in image plotter, minor additions to trace plotter.
- Added real-time binning and debounce filters.

#### 1.4.0

- Added Photometrics cameras and Cryocon temperature controllers.
- More consistent cameras interface: attributes properties, fast chunks (former `fastbuff`) readout, frame info formats.
- Added new simple GUI elements: multiline edits, enum labels.
- Expanded image and trace plotting widgets.
- Added linear transforms to data processing.
- Minor bugfixes in threading, GUI, devices.

#### 1.3.3

- Numpy loads bugfix (fixes compatibility with `numpy>=1.22`).

#### 1.3.2

- Added Leybold ITR90 and KJL300 pressure gauges.
- Minor bugfixes in threading and devices.

### 1.3.1

- Added expandable edit boxes and dialog containers.
- Improved Thorlabs devices compliance.
- Additional minor bugfixes in threading, GUI, devices.

### 1.3.0

- General
  - Minor speedups through calls caching.
  - Changed `muxcall` signature to allow multiple special argument values.
- Devices
  - Added Princeton Instruments cameras, IDS uEye cameras (as an option in uc480 cameras backend), Thorlabs Kinesis piezo motor controllers (e.g., KIM101) and quadrature photo-detector controllers (e.g., KPA101).
  - Added RS485 Arcus connection and a simple single-motor stage (DMX-J-SA).
  - Improved reliability if errors are encountered upon connection.
  - Multiple minor bug fixes and improved support of specific models.
- GUI
  - Added widgets: menu dropdown button, scroll area container, area highlighter.
  - Added querying element position and layout shape in layout widgets.
  - Added more utilities methods: querying containing layout, querying top-level parent, deleting widget.
- Threading
  - Added simple profiling through `yappi`.

### 1.2.1

- General
  - Added restarting methods for regular and threaded applications.
- Threading
  - Bugfixes in cameras and camera threads.
  - Bugfixes in streaming.

## 1.2.0

- General
  - Added `timing` context manager for simple code timing checks.
  - Improved RPyC wrapper logging and reliability.
  - Added Anaconda support.
  - Added minor network and file functions.
- Devices
  - Added Newport Picomotor 8742 motor controller, Toptica iBeam Smart laser, older version of Thorlabs FW motorized filter wheel.
  - Added camera frame output format (list or array).
  - Added `use_cavity` option to M2 Solstis laser.
  - Added method for auto-detecting associations between PhotonFocus cameras and frame grabbers.
  - Updated some generic classes (DCAM cameras, Thorlabs TLCamera cameras).
  - Updated SCPI failsafe operation, improved Thorlabs FW reliability.
  - Fixed several minor bugs.
- GUI
  - Rewritten GUI values handling to pass calls in a hierarchical manner. This makes the operation more predictable and overloading the behavior a bit easier.
  - Added out-of-range value action for combo boxes.
  - Fixed `ImagePlotter` incompatibility with the newer `pyqtgraph` versions, added separate x and y axis line cuts selection.
  - Minor layout handling bugfixes.
- Threading
  - Released advanced threading functionality: table/frame streaming, device threads, basic frame processing.
  - Task thread additions: delayed batch job stopping, context manager for task loop pausing.
  - Added argument-dependent call queue limit.
  - Improved threading speed and stability.

## 1.1.0

- General
  - Reorganized the core modules import structure: now `__init__.py` modules are mostly empty, and all the necessary imports are either exposed directly in `pylablib` (e.g., `pylablib.Fitter`), or should be accessed directly by the module (e.g. `p11.core.dataproc.fitting.Fitter`). Intermediate access (e.g., `p11.core.dataproc.Fitter`) is no longer supported.
  - File IO functions (e.g., `read_csv`) can now take file-like objects in addition to paths.
- Devices
  - Added Silicon Software frame grabbers interface and rearranged PhotonFocus code to include both IMAQ and SiliconSoftware frame grabbers.



- Fixed various compatibility bugs arising for specific versions of Python or dependency modules: Kinesis error with specific pyft232 versions, some DLL-dependent devices errors with Python 3.8+, DLL types in 32-bit Python.
- Addressed issue with occasional uc480 acquisition restarts, fixed M2 communication report errors.
- GUI and threading
  - Added container and layout management classes in addition to parameter tables for more consistent GUI structure organization.
  - Added `pylablib.widgets` module which combines all custom widgets for the ease of using in layout managers or custom applications.
  - Fixed support for PySide2 Qt5 backed.
  - Renamed `setupUi` -> `setup` for all widgets, and changed the GUI setup organization for many of them (the functioning stayed the same).
  - Reorganized scheduling in `QTaskThread` to treat jobs, commands, and subscriptions more consistently.
  - Added basic data stream management.

## 1.0.0

There have been too many alterations to list here comprehensively. Below is the list of the largest changes.

- General
  - Removed built-in `DataTable` class (together with `core.datatable` subpackage) in favor of pandas.
  - Renamed file IO functions: instead of generic `load` and `save` methods there are now more specific `loadfile.load_csv()`, `loadfile.load_dict()`, etc.
  - Removed some legacy modules which are not used in the rest of the library.
  - Renamed or moved certain modules: `core.utils.rpyc` -> `core.utils.rpyc_utils`, `core.fileio.logfile` -> `core.fileio.table_stream`, `core.fileio.binio` -> `core.utils.binio`, `core.devio.backend` -> `core.devio.backencd_comm`, `core.devio.untis` -> `core.utils.units`, `core.dataproc.waveforms` -> `core.dataproc.utils`
- Devices
  - Some legacy devices have been removed, since without access to the hardware it is hard to maintain and expand them. These include most of Agilent devices (33502A amplifier, N9310A microwave generator, HP 8712B and HP 8722D network analyzers, HP 8168F laser), Rigol DSA1030A spectrum analyzer, Tektronix MDO3000 oscilloscope, Vaunix LabBrick generators, Zurich Instruments HF2 and UHF, Andor Shamrock spectrographs (should be restored in future releases), NuPhoton NP2000 EDFA, PurePhotonics PPCL200 laser, Sirah Matisse laser (should be restored in future releases), Thorlabs PM100 power meter (should be restored in future releases), Lakeshore 370 resistance bridge (should be restored in future releases), MKS 900-series pressure gauges, and some custom devices (Arduino and Olimex AVR boards and Janis-related hardware).
  - The main devices package has been moved from `pylablib.aux_libs.devices` (which now refers to the legacy code) to `pylablib.devices`. Module organization has also changed slightly. To find the required modules and device class names, see the [devices list](#).
  - Lots of devices' interface has varied slightly, to make the interface more uniform and compatible between different kinds of devices. The changes are usually fairly straightforward (e.g., `move_to` instead of `move`). In many cases the interface was also expanded to include additional available methods.
  - Several devices have been added, generalized, or restructured:

- \* Combined Thorlabs KDC101 and K10CR1 into a single class `pylablib.devices.Thorlabs.BasicKinesisDevice`, which also accommodates similar kinds of devices.
- \* Added Arcus Performax2EXStage device for 2-axis controller with a slightly different interface (`pylablib.devices.Arcus.Performax2EXStage`)
- \* Added *several more AWGs* with similar interfaces
- Simplified the way external DLLs are *handled*
- Unified the *error handling*
- GUI and threading
  - Changed module structure
    - \* threading and GUI are now separate sub-packages `core.thread` and `core.gui`
    - \* all widgets are available simply through `pylablib.widgets` (simplifies integration with Qt Designer)
    - \* moved parameter tables widgets to the core library
  - Renamed some widgets to remove the LV prefix.
  - Interfaces changes in some of the classes: thread controllers, parameter tables, value tables. The changes are mostly cosmetics and involve names and parameters order. Most important changes:
    - \* thread controller methods: `subscribe` -> `subscribe_sync`, `sync_exec` -> `sync_exec_point`,
    - \* thread controller command/query shortcut: `.c` -> `.ca`, `.q` -> `.cs`, `.qi` -> `.csi`, `.qs` -> `.css`
    - \* thread controller variable access uses `.v` shortcut, i.e., instead of `ctl[name]` it is now `ctl.v[name]`
    - \* GUI value storage `ValuesTable/IndicatorValuesTable` are now combined and named as `GUIValues`
    - \* `ParamTable` and `GUIValues` uses `.h` shortcut to access value handlers, i.e., instead of `table[name]` it is now `table.h[name]`
    - \* `ParamTable`, `ImagePlotterCtl`, `TracePlotterCtl` constructor arguments: `display_table` -> `gui_values`, `display_table_root` -> `gui_values_root`
    - \* value-changed signal names in `ParamTable` and `GUIValues`: `changed_event` -> `get_value_changed_signal`
    - \* value-changed signal names in value handlers: `value_changed_signal` -> `get_value_changed_signal`
    - \* `ParamTable` methods: `lock` -> `set_enabled`, `add_button(checkable=True)` -> `add_toggle_button`
    - \* `NumEdit` and `NumLabel` methods: `set_number_format` -> `set_formatter`, `set_number_limit` -> `set_limiter` (the call signature also changed)
    - \* renamed signals to multicasts to avoid confusion with built-in Qt signals. Leads to `ThreadController.send_signal` -> `send_multicast`, `ThreadController.process_signal` -> `process_multicast`, `ThreadController` constructor argument `signal_pool` -> `multicast_pool`, class `SignalPool` -> `MulticastPool`, `QSignalThreadCallScheduler` -> `QMulticastThreadCallScheduler`.

## 2.6.2 Version 0.x

### 0.4.1

#### Interface changes

- Slightly changed representations of complex number in to-string conversions depending on the conversion rules ("python" vs "text").

#### Additions

- Devices
  - Added Thorlabs K10CR1 rotational stage (`legacy.aux_libs.devices.Thorlabs.K10CR1`)
  - Added Andor Shamrock spectrographs (`legacy.aux_libs.devices.AndorShamrock`)
  - Expanded Agilent AWG class
  - Added more 32bit dlls
  - Added `list_resources` method to every backend class, which lists available connections for this backend (not available for every backend; so far only works in `legacy.core.devio.backed.VisaDeviceBackend`, `legacy.core.devio.backed.SerialDeviceBackend`, and `legacy.core.devio.backed.FT232BackendOpenError`).
- GUI and threading
  - Added `legacy.aux_libs.gui.helpers.TableAccumulatorThread.preprocess_data` method to pre-process incoming data before adding it to the table
  - Added `update_only_on_visible` argument to `legacy.aux_libs.gui.widgets.trace_plotter.TracePlotter.setupUi` method, and `legacy.aux_libs.gui.widgets.trace_plotter.TracePlotter.get_required_channels` method.

### 0.4.0

#### Interface changes

- Dictionary entries (`legacy.core.fileio.dict_entry`) system has been slightly redesigned: building entries from stored objects has been moved from `legacy.core.fileio.dict_entry.IDictionaryEntry.build_entry` class method to a dedicated function `legacy.core.fileio.dict_entry.build_entry`, and entry classes have been added.
- `legacy.aux_libs.gui.helpers.StreamFormerThread` architecture changes, so that it can accumulate several rows before adding them into the storage; this lead to replacement of `legacy.aux_libs.gui.helpers.StreamFormerThread.prepare_new_row` method by `legacy.aux_libs.gui.helpers.StreamFormerThread.prepare_new_data`.

#### Additions

- General
  - Added pandas support in a bunch of places: loading/saving tables and dictionaries; data processing routines in `legacy.core.dataproc`; conversion of `legacy.core.dataproc.datatable.DataTable` and `legacy.core.utils.dictionary.Dictionary` object to/from pandas dataframes.
  - Expanded string conversion to support more explicit variable classes. For example, a numpy array `np.array([1,2,3])` can be converted into a string `'array([1, 2, 3])'` instead of a more ambiguous string `'[1, 2, 3]'` (which can also be a list). This behavior is controlled by a new argument `use_classes` in string conversion functions (such as `legacy.core.utils.string.to_string`)

and `legacy.core.utils.string.from_string`) and an argument `use_rep_classes` in file saving (`legacy.core.fileio.savefile.save`)

- Added general library parameters, which can be accessed via `pylablib.par` (works as a dictionary object). So far there's only one supported parameter: the default return type of the CSV file reading (can be "pandas" for pandas dataframe, "table" for `legacy.core.dataproc.datatable.DataTable` object, or "array" for raw numpy array).

- Devices

- Added LaserQuantum Finesse device class (`legacy.aux_libs.devices.devices.LaserQuantum`)
- NI DAQ now supports output of waveforms
- Added `legacy.aux_libs.devices.PCO_SC2.reset_api` and `legacy.aux_libs.devices.PCO_SC2.PCOSC2Camera.reboot` methods for resetting API and cameras
- Added `legacy.aux_libs.devices.Thorlabs.list_kinesis_devices` function to list connected Kinesis devices
- Added serial communication methods for IMAQ cameras (`legacy.aux_libs.devices.IMAQ.IMAQCamera`)

- GUI and threading

- Added line plotter (`legacy.aux_libs.gui.widgets.line_plotter`) and trace plotter (`legacy.aux_libs.gui.widgets.trace_plotter`) widgets
- Added virtual elements to value tables and parameter tables
- Added `gui_thread_safe` parameter to value tables and parameter tables. Enabling it make most common methods thread-safe (i.e., transparently called from the GUI thread)
- Added a corresponding `legacy.core.gui.qt.thread.controller.gui_thread_method` wrapper to implement the change above
- Added functional thread variables (`legacy.core.gui.qt.thread.controller.QThreadController.set_func_variable`)

- File saving / loading

- Added notation for dictionary files to include nested structures ('prefix blocks'). This lets one avoid common path prefix in stored dictionary files. For example, a file

```
some/long/prefix/x 1
some/long/prefix/y 2
some/long/prefix/y 3
```

can be represented as

```
//some/long/prefix
  x 1
  y 2
  z 3
///
```

The meaningful elements are `//some/long/prefix` line denoting that following elements have the given prefix, and `///` line denoting that the prefix block is done (indentation is only added for clarity).

- New dictionary entries: `dict_entry.ExternalNumpyDictionaryEntry` (external numpy array, can have arbitrary number of dimensions) and `dict_entry.ExpandedContainerDictionaryEntry` (turns

lists, tuples and dicts into dictionary branches, so that their content can benefit from the automatic table inlining, dictionary entry classes, etc.).

- Data processing
  - `legacy.core.dataproc.fitting.Fitter` now takes default scale and limit as constructor arguments.
  - `legacy.core.dataproc.feature.multi_scale_peakdet` has new `norm_ratio` argument.
  - `legacy.core.dataproc.image.get_region` and `legacy.core.dataproc.image.get_region_sum` take axis argument.
- Miscellaneous
  - Functions introspection module now supports Python 3 - style functions, and added a new function `legacy.core.utils.functions.funcsig`
  - `legacy.core.utils.general.StreamFileLogger` supports multiple destination paths
  - New network function `legacy.core.utils.net.get_all_local_addr` (return list of all local addresses on all interfaces) and `legacy.core.utils.net.get_local_hostname`

## 2.7 pylablib

### 2.7.1 pylablib package

#### Subpackages

#### `pylablib.core` package

#### Subpackages

#### `pylablib.core.dataproc` package

#### Submodules

#### `pylablib.core.dataproc.callable` module

**class** `pylablib.core.dataproc.callable.ICallable`

Bases: `object`

Fit function generalization.

Has a set of mandatory argument with no default values and a set of parameters with default values (there may or may not be an explicit list of them).

All the arguments are passed explicitly by name. Passed value supersede default values. Extra arguments (not used in the calculations) are ignored.

Assumed (but not enforced) to be immutable: changes after creation can break the behavior.

Implements (possibly; depends on subclasses) call namelist binding boosting: if the function is to be called many times with the same parameter names list, one can first bind parameters list, and then call bound function with the corresponding arguments. This way, `callable(**p)` should be equivalent to `callable.bind(p.keys())(*p.values())`.

**has\_arg**(*arg\_name*)

Determine if the function has an argument *arg\_name* (of all 3 categories)

**filter\_args\_dict**(*args*)

Filter argument names dictionary to leave only the arguments that are used

**get\_mandatory\_args**()

Return list of mandatory arguments (these are the ones without default values)

**is\_mandatory\_arg**(*arg\_name*)

Check if the argument *arg\_name* is mandatory

**get\_arg\_default**(*arg\_name*)

Return default value of the argument *arg\_name*.

Raise `KeyError` if the argument is not defined or `ValueError` if it has no default value.

**bind**(*arg\_names*, *\*\*bound\_params*)

Bind function to a given parameters set, leaving *arg\_names* as free parameters (in the given order)

**class** `NamesBoundCall`(*func*, *names*, *bound\_params*)

Bases: `object`

**bind\_namelist**(*arg\_names*, *\*\*bound\_params*)

Bind namelist to boost subsequent calls.

Similar to `bind(arg_names)`, but bound function doesn't accept additional parameters and can be boosted.

**class** `pylablib.core.dataproc.callable.MultiplexedCallable`(*func*, *multiplex\_by*,  
*join\_method='stack'*)

Bases: `ICallable`

Multiplex a single callable based on a single parameter.

If the function is called with this parameter as an iterable, then the underlying callable will be called for each value of the parameter separately, and the results will be joined into a single array (if return the values are scalar, they're joined in 1D array; otherwise, they're joined using *join\_method*).

#### Parameters

- **func** (*callable*) – Function to be parallelized.
- **multiplex\_by** (*str*) – Name of the argument to be multiplexed by.
- **join\_method** (*str*) – Method for combining individual results together if they're non-scalars. Can be either 'list' (combine the results in a single list), 'stack' (combine using `numpy.column_stack()`, i.e., add dimension to the result), or 'concatenate' (concatenate the return values; the dimension of the result stays the same).

Multiplexing also makes use of call signatures for underlying function even if `__call__` is used.

Note that this operation is slow, and should be used only for high-dimensional multiplexing; for 1D case it's much better to just use numpy arrays as arguments and rely on numpy parallelizing.

**has\_arg**(*arg\_name*)

Determine if the function has an argument *arg\_name* (of all 3 categories)

**get\_mandatory\_args**()

Return list of mandatory arguments (these are the ones without default values)

**get\_arg\_default**(*arg\_name*)

Return default value of the argument *arg\_name*.

Raise `KeyError` if the argument is not defined or `ValueError` if it has no default value.

**class NamesBoundCall**(*func, names, bound\_params*)

Bases: `object`

**bind**(*arg\_names, \*\*bound\_params*)

Bind function to a given parameters set, leaving *arg\_names* as free parameters (in the given order)

**bind\_namelist**(*arg\_names, \*\*bound\_params*)

Bind namelist to boost subsequent calls.

Similar to `bind(arg_names)`, but bound function doesn't accept additional parameters and can be boosted.

**filter\_args\_dict**(*args*)

Filter argument names dictionary to leave only the arguments that are used

**is\_mandatory\_arg**(*arg\_name*)

Check if the argument *arg\_name* is mandatory

**class** `pylablib.core.dataproc.callable.JoinedCallable`(*funcs, join\_method='stack'*)

Bases: `ICallable`

Join several callables sharing the same arguments list.

The results will be joined into a single array (if return the values are scalar, they're joined in 1D array; otherwise, they're joined using *join\_method*).

#### Parameters

- **funcs** (`[callable]`) – List of functions to be joined together.
- **join\_method** (`str`) – Method for combining individual results together if they're non-scalars. Can be either 'list' (combine the results in a single list), 'stack' (combine using `numpy.column_stack()`, i.e., add dimension to the result), or 'concatenate' (concatenate the return values; the dimension of the result stays the same).

**has\_arg**(*arg\_name*)

Determine if the function has an argument *arg\_name* (of all 3 categories)

**get\_mandatory\_args**()

Return list of mandatory arguments (these are the ones without default values)

**get\_arg\_default**(*arg\_name*)

Return default value of the argument *arg\_name*.

Raise `KeyError` if the argument is not defined or `ValueError` if it has no default value.

**class NamesBoundCall**(*func, names, bound\_params*)

Bases: `object`

**bind**(*arg\_names, \*\*bound\_params*)

Bind function to a given parameters set, leaving *arg\_names* as free parameters (in the given order)

**bind\_namelist**(*arg\_names, \*\*bound\_params*)

Bind namelist to boost subsequent calls.

Similar to `bind(arg_names)`, but bound function doesn't accept additional parameters and can be boosted.

**filter\_args\_dict**(args)

Filter argument names dictionary to leave only the arguments that are used

**is\_mandatory\_arg**(arg\_name)

Check if the argument *arg\_name* is mandatory

**class** pylablib.core.dataproc.callable.**FunctionCallable**(func, function\_signature=None,  
defaults=None, alias=None)

Bases: *ICallable*

Callable based on a function or a method.

#### Parameters

- **func** – Function to be wrapped.
- **function\_signature** – A *functions.FunctionSignature* object supplying information about function's argument names and default values, if they're different from what's extracted from its signature.
- **defaults** (*dict*) – A dictionary {name: value} of additional default parameters values. Override the defaults from the signature. All default values must be pass-able to the function as a parameter
- **alias** (*dict*) – A dictionary {alias: original} for renaming some of the original arguments. Original argument names can't be used if aliased (though, multi-aliasing can be used explicitly, e.g., alias={'alias': 'arg', 'arg': 'arg'}). A name can be blocked (its usage causes error) if it's aliased to None (alias={'blocked\_name': None}).

Optional non-named arguments in the form \*args are not supported, since all the arguments are passed to the function by keywords.

Optional named arguments in the form \*\*kwargs are supported only if their default values are explicitly provided in defaults (otherwise it would be unclear whether argument should be added into \*\*kwargs or ignored altogether).

**has\_arg**(arg\_name)

Determine if the function has an argument *arg\_name* (of all 3 categories)

**get\_mandatory\_args**()

Return list of mandatory arguments (these are the ones without default values)

**get\_arg\_default**(arg\_name)

Return default value of the argument *arg\_name*.

Raise *KeyError* if the argument is not defined or *ValueError* if it has no default value.

**class** NamesBoundCall(func, names, bound\_params)

Bases: *object*

**bind**(arg\_names, \*\*bound\_params)

Bind function to a given parameters set, leaving *arg\_names* as free parameters (in the given order)

**bind\_namelist**(arg\_names, \*\*bound\_params)

Bind namelist to boost subsequent calls.

Similar to *bind(arg\_names)*, but bound function doesn't accept additional parameters and can be boosted.

**filter\_args\_dict**(args)

Filter argument names dictionary to leave only the arguments that are used



**is\_mandatory\_arg**(*arg\_name*)

Check if the argument *arg\_name* is mandatory

**class** `pylablib.core.dataproc.callable.MethodCallable`(*method*, *function\_signature=None*,  
*defaults=None*, *alias=None*)

Bases: `FunctionCallable`

Similar to `FunctionCallable`, but accepts class method instead of a function.

The only addition is that now object's attributes can also parameters to the function: all the parameters which are not explicitly mentioned in the method signature are assumed to be object's attributes.

The parameters are affected by alias, but NOT affected by defaults (since it's impossible to ensure that all object's attributes are kept constant, and it's impractical to reset them all to default values at every function call).

#### Parameters

- **method** – Method to be wrapped.
- **function\_signature** – A `functions.FunctionSignature` object supplying information about function's argument names and default values, if they're different from what's extracted from its signature. If it's assumed that the first self argument is already excluded.
- **defaults** (*dict*) – A dictionary {*name*: *value*} of additional default parameters values. Override the defaults from the signature. All default values must be pass-able to the function as a parameter
- **alias** (*dict*) – A dictionary {*alias*: *original*} for renaming some of the original arguments. Original argument names can't be used if aliased (though, multi-aliasing can be used explicitly, e.g., `alias={'alias': 'arg', 'arg': 'arg'}`). A name can be blocked (its usage causes error) if it's aliased to None (`alias={'blocked_name': None}`).

This callable is implemented largely to be used with `TheoryCalculator` class (currently deprecated).

**has\_arg**(*arg\_name*)

Determine if the function has an argument *arg\_name* (of all 3 categories)

**get\_arg\_default**(*arg\_name*)

Return default value of the argument *arg\_name*.

Raise `KeyError` if the argument is not defined or `ValueError` if it has no default value.

**class** `NamesBoundCall`(*func*, *names*, *bound\_params*)

Bases: `object`

**bind**(*arg\_names*, *\*\*bound\_params*)

Bind function to a given parameters set, leaving *arg\_names* as free parameters (in the given order)

**bind\_namelist**(*arg\_names*, *\*\*bound\_params*)

Bind namelist to boost subsequent calls.

Similar to `bind(arg_names)`, but bound function doesn't accept additional parameters and can be boosted.

**filter\_args\_dict**(*args*)

Filter argument names dictionary to leave only the arguments that are used

**get\_mandatory\_args**()

Return list of mandatory arguments (these are the ones without default values)

**is\_mandatory\_arg**(*arg\_name*)

Check if the argument *arg\_name* is mandatory

`pylablib.core.dataproc.callable.to_callable(func)`

Convert a function to an *ICallable* instance.

If it's already *ICallable*, return unchanged. Otherwise, return *FunctionCallable* or *MethodCallable* depending on whether it's a function or a bound method.

### `pylablib.core.dataproc.ctransform_fallback` module

**class** `pylablib.core.dataproc.ctransform_fallback.CLinear2DTransform(m=None, s=None)`

Bases: `object`

Pure Python implementation of Cython-based linear 2D transform

**copy()**

Copy the transform

**property** `tmatr`

Transform matrix as a 2x2 numpy array

**property** `svec`

Transform vector as a numpy array

**invert()**

Invert the transform

**precede(trans)**

Precede the transform with a different transform

**follow(trans)**

Follow the transform with a different transform

**i(x, y)**

Apply the inverse transform to the given point

**shift(s1, s2, preceded=False)**

Apply a shift transform before or after (default) the given transform

**multiply(m11, m12, m21, m22, preceded=False)**

Apply a matrix multiplication transform before or after (default) the given transform

**scale(s1, s2, preceded=False)**

Apply a scale transform before or after (default) the given transform

**transpose(preceded=False)**

Apply a transpose transform before or after (default) the given transform

**classmethod** `from_matr_shift(matr, shift)`

Build a transform from a 2x2 transform matrix and a shift vector

## pylablib.core.dataproc.feature module

Traces feature detection: peaks, baseline, local extrema.

**class** pylablib.core.dataproc.feature.**Baseline**(*position=0.0, width=1.0*)

Bases: [Baseline](#)

Baseline (background) for a trace.

*position* is the background level, and *width* is its noise width.

**position**

**width**

pylablib.core.dataproc.feature.**get\_baseline\_simple**(*trace, find\_width=True*)

Get the baseline of the 1D trace.

If *find\_width==True*, calculate its width as well.

pylablib.core.dataproc.feature.**subtract\_baseline**(*trace*)

Subtract baseline from the trace (make its background zero).

**class** pylablib.core.dataproc.feature.**Peak**(*position=0.0, height=1.0, width=1.0, kernel='generic'*)

Bases: [Peak](#)

A trace peak.

*kernel* defines its shape (for, e.g., generation purposes).

**height**

**kernel**

**position**

**width**

pylablib.core.dataproc.feature.**find\_peaks\_cutoff**(*trace, cutoff, min\_width=0, kind='peak', subtract\_bl=True*)

Find peaks in the data using cutoff.

### Parameters

- **trace** – 1D data array.
- **cutoff** (*float*) – Cutoff value for the peak finding.
- **min\_width** (*int*) – Minimal uninterrupted width (in datapoints) of a peak. Any peaks this width are ignored.
- **kind** (*str*) – Peak kind. Can be 'peak' (positive direction), 'dip' (negative direction) or 'both' (both directions).
- **subtract\_bl** (*bool*) – If True, subtract baseline of the trace before checking cutoff.

### Returns

List of [Peak](#) objects.

pylablib.core.dataproc.feature.**rescale\_peak**(*peak, xoff=0.0, xscale=1.0, yoff=0, yscale=1.0*)

Rescale peak's position, width and height.

*xscale* rescales position and width, *xoff* shifts position, *yscale* and *yoff* affect peak height.

`pylablib.core.dataproc.feature.peaks_sum_func(peaks, peak_func='lorentzian')`

Create a function representing sum of *peaks*.

*peak\_func* determines default peak kernel (used if `peak.kernel=="generic"`). Kernel is either a name string or a function taking 3 arguments (*x*, *width*, *height*).

`pylablib.core.dataproc.feature.get_kernel(width, kernel_width=None, kernel='lorentzian')`

Get a finite-sized kernel.

Return 1D array of length  $2*\text{kernel\_width}+1$  containing the given kernel. By default, `kernel_width=int(width*3)`.

`pylablib.core.dataproc.feature.get_peakdet_kernel(peak_width, background_width,  
kernel_width=None, kernel='lorentzian')`

Get a peak detection kernel.

Return 1D array of length  $2*\text{kernel\_width}+1$  containing the kernel. The kernel is a sum of narrow positive peak (with the width *peak\_width*) and a broad negative peak (with the width *background\_width*); both widths are specified in datapoints (index). Each peak is normalized to have unit sum, i.e., the kernel has zero total sum. By default, `kernel_width=int(background_width*3)`.

`pylablib.core.dataproc.feature.multi_scale_peakdet(trace, widths, background_ratio, kind='peak',  
norm_ratio=None, kernel='lorentzian')`

Detect multiple peak widths using `get_peakdet_kernel()` kernel.

#### Parameters

- **trace** – 1D data array.
- **widths** (*[float]*) – Array of possible peak widths.
- **background\_ratio** (*float*) – ratio of the *background\_width* to the *peak\_width* in `get_peakdet_kernel()`.
- **kind** (*str*) – Peak kind. Can be 'peak' (positive direction) or 'dip' (negative direction).
- **norm\_ratio** (*float*) – if not None, defines the width of the “normalization region” (in units of the kernel width, same as for the background kernel); it is then used to calculate a local trace variance to normalize the peaks magnitude.
- **kernel** – Peak matching kernel.

#### Returns

Filtered trace which shows peak ‘affinity’ at each point.

`pylablib.core.dataproc.feature.find_local_extrema(wf, region_width=3, kind='max',  
min_distance=None)`

Find local extrema (minima or maxima) of 1D trace.

*kind* can be "min" or "max" and determines the kind of the extrema. Local minima (maxima) are defined as points which are smaller (greater) than all other points in the region of width *region\_width* around it. *region\_width* is always round up to an odd integer. *min\_distance* defines the minimal distance between the extrema ( $\text{region\_width}/2$  by default). If there are several extrema within *min\_distance*, their positions are averaged together.

`pylablib.core.dataproc.feature.latching_trigger(wf, threshold_on, threshold_off, init_state='undef',  
result_kind='separate')`

Determine indices of rise and fall trigger events with hysteresis (latching) thresholds.

Return either two arrays (`rise_trig`, `fall_trig`) containing trigger indices (if `result_kind=="separate"`), or a single array of tuples `[(dir,pos)]`, where *dir* is the trigger direction (+1 or -1) and *pos* is its index (if `result_kind=="joined"`). Triggers happen when a state switch from 'high' to 'low' (rising) or vice versa (falling). The state switches from 'low' to 'high' when the trace value goes above *threshold\_on*, and from 'high' to 'low' when the trace value goes below *threshold\_off*. For a stable hysteresis effect, *threshold\_on* should be larger than *threshold\_off*, which means that the trace values between these two thresholds can not change the state. *init\_state* specifies the initial state: "low", "high", or "undef" (undefined state).

## pylablib.core.dataproc.filters module

Routines for filtering arrays (mostly 1D data).

`pylablib.core.dataproc.filters.convolve1d(trace, kernel, mode='reflect', cval=0.0)`

Convolution filter.

Convolves *trace* with the given *kernel* (1D array). *mode* and *cval* determine how the endpoints are handled. Simply a wrapper around the standard `scipy.ndimage.convolve1d()` that handles complex arguments.

`pylablib.core.dataproc.filters.convolution_filter(a, width, kernel='gaussian', kernel_span='auto', mode='reflect', cval=0.0, kernel_height=None)`

Convolution filter.

### Parameters

- **a** – array for filtering.
- **width** (*float*) – kernel width (second parameter to the kernel function).
- **kernel** – either a string defining the kernel function (see `specfunc.get_kernel_func()` for possible kernels), or a function taking 3 arguments (*pos*, *width*, *height*), where *height* can be `None` (assumes normalization by area).
- **kernel\_span** – the cutoff for the kernel function. Either an integer (number of points) or 'auto' (autodetect for "gaussian", "rectangle" and "exp\_decay", full trace width for all other kernels).
- **mode** (*str*) – convolution mode (see `scipy.ndimage.convolve()`).
- **cval** (*float*) – convolution fill value (see `scipy.ndimage.convolve()`).
- **kernel\_height** – height parameter to be passed to the kernel function. `None` means normalization by area.

`pylablib.core.dataproc.filters.gaussian_filter(a, width, mode='reflect', cval=0.0)`

Simple gaussian filter. Can handle complex data.

Equivalent to a convolution with a gaussian. Equivalent to `scipy.ndimage.gaussian_filter1d()`, uses `convolution_filter()`.

`pylablib.core.dataproc.filters.gaussian_filter_nd(a, width, mode='reflect', cval=0.0)`

Simple gaussian filter. Can't handle complex data.

Equivalent to a convolution with a gaussian. Wrapper around `scipy.ndimage.gaussian_filter()`.

`pylablib.core.dataproc.filters.low_pass_filter(trace, t, mode='reflect', cval=0.0)`

Simple single-pole low-pass filter.

*t* is the filter time constant, *mode* and *cval* are the trace expansion parameters (only from the left). Implemented as a recursive digital filter, so its performance doesn't depend strongly on *t*. Works only for 1D arrays.

`pylablib.core.dataproc.filters.high_pass_filter(trace, t, mode='reflect', cval=0.0)`

Simple single-pole high-pass filter (equivalent to subtracting a low-pass filter).

*t* is the filter time constant, *mode* and *cval* are the trace expansion parameters (only from the left). Implemented as a recursive digital filter, so its performance doesn't depend strongly on *t*. Works only for 1D arrays.

`pylablib.core.dataproc.filters.integrate(trace)`

Calculate the integral of the trace.

Alias for `numpy.cumsum()`.

`pylablib.core.dataproc.filters.differentiate(trace)`

Calculate the differential of the trace.

Note that since the data dimensions are changed (length is reduced by 1), the index is not preserved for pandas DataFrames.

`pylablib.core.dataproc.filters.sliding_average(a, width, mode='reflect', cval=0.0)`

Simple sliding average filter

Equivalent to convolution with a rectangle peak function.

`pylablib.core.dataproc.filters.median_filter(a, width, mode='reflect', cval=0.0)`

Median filter.

Wrapper around `scipy.ndimage.median_filter()`.

`pylablib.core.dataproc.filters.sliding_filter(trace, n, dec='bin', mode='reflect', cval=0.0)`

Perform sliding filtering on the data.

#### Parameters

- **trace** – 1D array-like object.
- **n** (*int*) – bin width.
- **dec** (*str*) – decimation method. Can be - 'bin' or 'mean' - do a binning average; - 'sum' - sum points; - 'min' - leave min point; - 'max' - leave max point; - 'median' - leave median point (works as a median filter). - a function which takes a single 1D array and compresses it into a number
- **mode** (*str*) – Expansion mode. Can be 'constant' (added values are determined by *cval*), 'nearest' (added values are end values of the trace), 'reflect' (reflect trace with respect to its endpoint) or 'wrap' (wrap the values from the other size).
- **cval** (*float*) – If mode=='constant', determines the expanded values.

`pylablib.core.dataproc.filters.decimate(a, n, dec='skip', axis=0, mode='drop')`

Decimate the data.

Note that since the data dimensions are changed, the index is not preserved for pandas DataFrames.

#### Parameters

- **a** – data array.
- **n** (*int*) – decimation factor.
- **dec** (*str*) – decimation method. Can be - 'skip' - just leave every n'th point while completely omitting everything else; - 'bin' or 'mean' - do a binning average; - 'sum' - sum points; - 'min' - leave min point; - 'max' - leave max point; - 'median' - leave median point (works as a median filter). - a function which takes two arguments (nD numpy array and an axis) and compresses the array along the given axis

- **axis** (*int*) – axis along which to perform the decimation; can also be a tuple, in which case the same decimation is performed sequentially along several axes.
- **mode** (*str*) – determines what to do with the last bin if it's incomplete. Can be either 'drop' (omit the last bin) or 'leave' (keep it).

`pylablib.core.dataproc.filters.binning_average(a, width, axis=0, mode='drop')`

Binning average filter.

Equivalent to `decimate()` with `dec=='bin'`.

`pylablib.core.dataproc.filters.decimate_full(a, dec='skip', axis=0)`

Completely decimate the data along a given axis.

#### Parameters

- **a** – data array.
- **dec** (*str*) – decimation method. Can be - 'skip' - just leave every n'th point while completely omitting everything else; - 'bin' or 'mean' - do a binning average; - 'sum' - sum points; - 'min' - leave min point; - 'max' - leave max point; - 'median' - leave median point (works as a median filter). - a function which takes two arguments (nD numpy array and an axis) and compresses the array along the given axis
- **axis** (*int*) – axis along which to perform the decimation; can also be a tuple, in which case the same decimation is performed along several axes.

`pylablib.core.dataproc.filters.decimate_datasets(arrs, dec='mean')`

Decimate datasets with the same shape element-wise (works only for 1D or 2D arrays).

Note that the index data is taken from the first array in the list.

`dec` has the same values and meaning as in `decimate()`. The format of the output (numpy or pandas, and the name of columns in pandas DataFrame) is determined by the first array in the list.

`pylablib.core.dataproc.filters.collect_into_bins(values, distance, preserve_order=False, to_return='value')`

Collect all values into bins separated at least by `distance`.

Return the extent of each bin. If `preserve_order==False`, values are sorted before splitting. If `to_return="value"`, the extent is given in values; if `to_return="index"`, it is given in indices (only useful if `preserve_order=True`, as otherwise the indices correspond to a sorted array). If `distance` is a tuple, then it denotes the minimal and the maximal separation between consecutive elements; otherwise, it is a single number denoting maximal absolute distance (i.e., it corresponds to a tuple `(-distance, distance)`).

`pylablib.core.dataproc.filters.split_into_bins(values, max_span, max_size=None)`

Split values into bins of the span at most `max_span` and number of elements at most `max_size`.

If `max_size` is `None`, it's assumed to be infinite. Return array of indices for each bin. Values are sorted before splitting.

`pylablib.core.dataproc.filters.fourier_filter(trace, response, dt=1, preserve_real=True)`

Apply filter to a trace in the frequency domain.

`response` is a (possibly) complex function with single 1D real numpy array as a frequency argument. `dt` specifies time step between consecutive points. Note that in case of a multi-column data the filter is applied column-wise; this is in contrast with the Fourier transform methods, which would assume the first column to be times.

If `preserve_real==True`, then the `response` for negative frequencies is automatically taken to be complex conjugate of the `response` for positive frequencies (so that the real trace stays real).

`pylablib.core.dataproc.filters.fourier_make_response_real(response)`

Turn a frequency filter function into a real one (in the time domain).

Done by reflecting and complex conjugating positive frequency part to negative frequencies. *response* is a function with a single argument (frequency), return value is a modified function.

`pylablib.core.dataproc.filters.fourier_filter_bandpass(pass_range_min, pass_range_max)`

Generate a bandpass filter function (hard cutoff).

The function is symmetric, so that it corresponds to a real response in time domain.

`pylablib.core.dataproc.filters.fourier_filter_bandstop(stop_range_min, stop_range_max)`

Generate a bandstop filter function (hard cutoff).

The function is symmetric, so that it corresponds to a real response in time domain.

**class** `pylablib.core.dataproc.filters.RunningDecimationFilter(n, mode='mean',  
on_incomplete='none')`

Bases: `object`

Running decimation filter.

Remembers last *n* samples and returns their averages, median, etc.

#### Parameters

- **n** – decimation length
- **mode** – decimation mode ("mean", "median", "min", or "max")
- **on\_incomplete** – determines what to return while the filter window is not yet full; can be "none" (default, return None), or "partial" (operate on the partial accumulated data)

**get()**

Get the filtered result

**add(x)**

Add a new sample

**reset()**

Reset the filter

**class** `pylablib.core.dataproc.filters.RunningDebounceFilter(n, precision=None, initial=None)`

Bases: `object`

Running debounce filter.

“Sticks” to the current value and only switches when a new value remains constant (withing a given precision) for a given number of samples. Filters out temporary spikes and short changes, conceptually similar to a running median filter.

#### Parameters

- **n** – length of the required constant period
- **precision** – comparison precision (None means that the values should be exactly equal)
- **initial** – initial value; None means that the first sample sets this value

**get()**

Get the filtered result



**add(*x*)**

Add a new sample

**reset()**

Reset the filter

## pylablib.core.dataproc.fitting module

Universal function fitting interface.

```
class pylablib.core.dataproc.fitting.Fitter(func, xarg_name=None, fit_parameters=None,
                                           fixed_parameters=None, scale=None, limits=None,
                                           weights=None)
```

Bases: `object`

Fitter object.

Can handle variety of different functions, complex arguments or return values, array arguments.

### Parameters

- **func** (*callable*) – Fit function. Can be anything callable (function, method, object with `__call__` method, etc.).
- **xarg\_name** (*str* or *list*) – Name (or multiple names) for x arguments. These arguments are passed to *func* (as named arguments) when calling for fitting. Can be a string (single argument) or a list (arbitrary number of arguments, including zero).
- **fit\_parameters** (*dict*) – Dictionary {*name*: *value*} of parameters to be fitted (*value* is the starting value for the fitting procedure). If *value* is None, try and get the default value from the *func*.
- **fixed\_parameters** (*dict*) – Dictionary {*name*: *value*} of parameters to be fixed during the fitting procedure. If *value* is None, try and get the default value from the *func*.
- **scale** (*dict*) – Defines typical scale of fit parameters (used to normalize fit parameters supplied of `scipy.optimize.least_squares()`). Note: for complex parameters scale must also be a complex number, with re and im parts of the scale variable corresponding to the scale of the re and im part.
- **limits** (*dict*) – Boundaries for the fit parameters (missing entries are assumed to be unbound). Each boundary parameter is a tuple (*lower*, *upper*). *lower* or *upper* can be None, `numpy.nan` or `numpy.inf` (with the appropriate sign), which implies no bounds in the given direction. Note: for compound data types (such as lists) the entries are still tuples of 2 elements, each of which is either None (no bound for any sub-element) or has the same structure as the full parameter. Note: for complex parameters limits must also be complex numbers (or None), with re and im parts of the limits variable corresponding to the limits of the re and im part.
- **weights** (*list* or *numpy.ndarray*) – Determines the weights of y-points. Can be either an array broadcastable to y (e.g., a scalar or an array with the same shape as y), in which case it's interpreted as list of individual point weights (which multiply residuals before they are squared). Or it can be an array with number of elements which is square of the number of elements in y, in which case it's interpreted as a weights matrix (which matrix-multiplies residuals before they are squared).

**set\_xarg\_name**(*xarg\_name*)

Set names of x arguments.

Can be a string (single argument) or a list (arbitrary number of arguments, including zero).

**use\_xarg**()

Return True if the function requires x arguments

**set\_fixed\_parameters**(*fixed\_parameters*)

Change fixed parameters

**update\_fixed\_parameters**(*fixed\_parameters*)

Update the dictionary of fixed parameters

**del\_fixed\_parameters**(*fixed\_parameters*)

Remove fixed parameters

**set\_fit\_parameters**(*fit\_parameters*)

Change fit parameters

**update\_fit\_parameters**(*fit\_parameters*)

Update the dictionary of fit parameters

**del\_fit\_parameters**(*fit\_parameters*)

Remove fit parameters

**fit**(*x=None, y=0, fit\_parameters=None, fixed\_parameters=None, scale='default', limits='default', weights=1.0, parscore=None, return\_stderr=False, return\_residual=False, \*\*kwargs*)

Fit the data.

#### Parameters

- **x** – x arguments. If the function has single x argument, x is an array-like object; otherwise, x is a list of array-like objects (can be None if there are no x parameters).
- **y** – Target function values.
- **fit\_parameters** (*dict*) – Adds to the default *fit\_parameters* of the fitter (has priority on duplicate entries).
- **fixed\_parameters** (*dict*) – Adds to the default *fixed\_parameters* of the fitter (has priority on duplicate entries).
- **scale** (*dict*) – Defines typical scale of fit parameters (used to normalize fit parameters supplied of `scipy.optimize.least_squares()`). Note: for complex parameters scale must also be a complex number, with re and im parts of the scale variable corresponding to the scale of the re and im part. If value is "default", use the value supplied on the fitter creation (by default, no specific scales).
- **limits** (*dict*) – Boundaries for the fit parameters (missing entries are assumed to be unbound). Each boundary parameter is a tuple (*lower*, *upper*). *lower* or *upper* can be None, `numpy.nan` or `numpy.inf` (with the appropriate sign), which implies no bounds in the given direction. Note: for compound data types (such as lists) the entries are still tuples of 2 elements, each of which is either None (no bound for any sub-element) or has the same structure as the full parameter. Note: for complex parameters limits must also be complex numbers (or None), with re and im parts of the limits variable corresponding to the limits of the re and im part. If value is "default", use the value supplied on the fitter creation (by default, no limits).

- **weights** (*list* or *numpy.ndarray*) – Determines the weights of y-points. Can be either an array broadcastable to y (e.g., a scalar or an array with the same shape as y), in which case it's interpreted as list of individual point weights (which multiply residuals before they are squared). Or it can be an array with number of elements which is square of the number of elements in y, in which case it's interpreted as a weights matrix (which matrix-multiplies residuals before they are squared). If value is "default", use the value supplied on the fitter creation (by default, no weights)
- **parscore** (*callable*) – parameter score function, whose value is added to the mean-square error (sum of all residuals squared) after applying weights. Takes the same parameters as the fit function, only without the x-arguments, and return an array-like value. Can be used for, e.g., 'soft' fit parameter constraining.
- **return\_stderr** (*bool*) – If True, append *stderr* to the output.
- **return\_residual** – If not False, append *residual* to the output.
- **\*\*kwargs** – arguments passed to `scipy.optimize.least_squares()` function.

#### Returns

(*params*, *bound\_func*[, *stderr*][, *residual*]):

- *params*: a dictionary {*name*: *value*} of the parameters supplied to the function (both fit and fixed).
- *bound\_func*: the fit function with all the parameters bound (i.e., it only requires x parameters).
- *stderr*: a dictionary {*name*: *error*} of standard deviation for fit parameters to the return parameters.  
If the fitting routine returns no residuals (usually for a bad or an under-constrained fit), all residuals are set to NaN.
- *residual*: either a full array of residuals `func(x, **params)-y` (if `return_residual=='full'`), a mean magnitude of the residuals `mean(abs(func(x, **params)-y)**2)` (if `return_residual==True` or `return_residual=='mean'`), or the total residuals including weights `mean(abs((func(x, **params)-y)*weights)**2)` (if `return_residual=='weighted'`).

#### Return type

*tuple*

**initial\_guess**(*fit\_parameters=None*, *fixed\_parameters=None*, *return\_stderr=False*, *return\_residual=False*)

Return the initial guess for the fitting.

#### Parameters

- **fit\_parameters** (*dict*) – Overrides the default *fit\_parameters* of the fitter.
- **fixed\_parameters** (*dict*) – Overrides the default *fixed\_parameters* of the fitter.
- **return\_stderr** (*bool*) – If True, append *stderr* to the output.
- **return\_residual** – If not False, append *residual* to the output.

#### Returns

(*params*, *bound\_func*).

- *params*: a dictionary {*name*: *value*} of the parameters supplied to the function (both fit and fixed).

- *bound\_func*: the fit function with all the parameters bound (i.e., it only requires x parameters).
- *stderr*: a dictionary {name: error} of standard deviation for fit parameters to the return parameters.  
Always zero, added for better compatibility with *fit()*.
- *residual*: either a full array of residuals *func(x, \*\*params)-y* (if *return\_residual=='full'*) or a mean magnitude of the residuals *mean(abs(func(x, \*\*params)-y)\*\*2)* (if *return\_residual==True* or *return\_residual=='mean'*). Always zero, added for better compatibility with *fit()*.

**Return type**

tuple

```
pylablib.core.dataproc.fitting.huge_error(x, factor=100.0)
```

```
pylablib.core.dataproc.fitting.get_best_fit(x, y, fits)
```

Select the best (lowest residual) fit result.

*x* and *y* are the argument and the value of the bound fit function. *fits* is the list of fit results (tuples returned by *Fitter.fit()*).

**pylablib.core.dataproc.fourier module**

Routines for Fourier transform.

```
pylablib.core.dataproc.fourier.get_prev_len(l, maxprime=7)
```

Get the largest number less or equal to *l*, which is composed of prime factors up to *maxprime*.

So far, only *maxprime* of 2, 3, 5, 7 and 11 are supported. *maxprime* of 5 gives less than 15% length reduction (and less than 6% for lengths above 400). *maxprime* of 11 gives less than 8% length reduction (and less than 4% for lengths above 300).

```
pylablib.core.dataproc.fourier.truncate_trace(trace, maxprime=7)
```

Truncate trace length to the nearest smaller length which is composed of prime factors up to *maxprime*.

So far, only *maxprime* of 2, 3, 5, 7 and 11 are supported. *maxprime* of 5 gives less than 15% length reduction (and less than 6% for lengths above 400). *maxprime* of 11 gives less than 8% length reduction (and less than 4% for lengths above 300).

```
pylablib.core.dataproc.fourier.normalize_fourier_transform(ft, normalization='none', df=None,
                                                           copy=False)
```

Normalize the Fourier transform data.

*ft* is a 1D trace or a 2D array with 2 columns: frequency and complex amplitude. *normalization* can be 'none' (standard numpy normalization), 'sum' (the power sum is preserved: *sum(abs(ft)\*\*2)==sum(abs(trace)\*\*2)*), 'rms' (the power sum is equal to the trace RMS power: *sum(abs(ft)\*\*2)==mean(abs(trace)\*\*2)*), 'density' (power spectral density normalization, *sum(abs(ft[:,1])\*\*2)\*df==mean(abs(trace[:,1])\*\*2)*), or 'dBc' (same as 'density', but normalized by the mean of the trace) If *normalization=='density'*, then *df* can specify the frequency step between two consecutive bins; if *df* is None, it is extracted from the first two points of the frequency axis (or set to 1, if *ft* is a 1D trace)

```
pylablib.core.dataproc.fourier.apply_window(trace_values, window='rectangle',
                                             window_power_compensate=True)
```

Apply FT window to the trace.

If `window_power_compensate==True`, multiply the data is multiplied by a compensating factor to preserve power in the spectrum.

```
pylablib.core.dataproc.fourier.fourier_transform(trace, dt=None, truncate=False,
                                                normalization='none', single_sided=False,
                                                window='rectangle',
                                                window_power_compensate=True, raw=False)
```

Calculate a fourier transform of the trace.

#### Parameters

- **trace** – Time trace to be transformed. It can be a 1D trace of values, a 2-column trace, or a 3-column trace. If `dt` is `None`, then the first column is assumed to be time (only support uniform time step), and the other columns are either the trace values (for a single data column) or real and imaginary parts of the trace (for two data columns). If `dt` is not `None`, then the time column is assumed to be missing, so the two columns are assumed to be the real and the imaginary parts.
- **dt** – if not `None`, can specify the time step between the consecutive samples, in which case it is assumed that the time column is missing from the trace; otherwise, try to get it from the time column of the trace if it exists, or set to 1 otherwise.
- **truncate** (*bool or int*) – Determines whether to truncate the trace to the nearest product of small primes (speeds up FFT algorithm); can be `False` (no truncation), an integer 2, 3, 5, 7, or 11 (truncate to a product of primes up to and including this number), or `True` (default prime factorization, currently set to 7)
- **normalization** (*str*) – Fourier transform normalization: - `'none'`: no (i.e., default numpy) normalization; - `'sum'`: the norm of the data is conserved (`sum(abs(ft[:, 1])**2)==sum(abs(trace[:, 1])**2)`); - `'rms'`: sum of the PSD is equal to the RMS trace amplitude squared (`sum(abs(ft[:, 1])**2)==mean(abs(trace[:, 1])**2)`); - `'density'`: power spectral density normalization, in `x/rtHz` (`sum(abs(ft[:, 1])**2)*df==mean(abs(trace[:, 1])**2)`); - `'dBc'`: like `'density'`, but normalized to the mean trace value.
- **single\_sided** (*bool*) – If `True`, only leave positive frequency side of the transform.
- **window** (*str*) – FT window. Can be `'rectangle'` (essentially, no window), `'hann'` or `'hamming'`.
- **window\_power\_compensate** (*bool*) – If `True`, the data is multiplied by a compensating factor to preserve power in the spectrum.
- **raw** (*bool*) – if `True`, return a simple 1D trace with the result.

#### Returns

a two-column array of the same kind as the input, where the first column is frequency, and the second is complex FT data.

```
pylablib.core.dataproc.fourier.flip_fourier_transform(ft)
```

Flip the fourier transform (analogous to making frequencies negative and flipping the order).

```
pylablib.core.dataproc.fourier.inverse_fourier_transform(ft, df=None, truncate=False,
                                                         zero_loc=None, symmetric_time=False,
                                                         raw=False)
```

Calculate an inverse fourier transform of the trace.

#### Parameters

- **ft** – Fourier transform data to be inverted. It can be a 1D trace of values, a 2-column trace, or a 3-column trace. If *df* is `None`, then the first column is assumed to be frequency (only support uniform frequency step), and the other columns are either the trace values (for a single data column) or real and imaginary parts of the trace (for two data columns). If *df* is not `None`, then the frequency column is assumed to be missing, so the two columns are assumed to be the real and the imaginary parts.
- **df** – if not `None`, can specify the frequency step between the consecutive samples; otherwise, try to get it from the frequency column of the trace if it exists, or set to 1 otherwise.
- **truncate** (*bool* or *int*) – Determines whether to truncate the trace to the nearest product of small primes (speeds up FFT algorithm); can be `False` (no truncation), an integer 2, 3, 5, 7, or 11 (truncate to a product of primes up to and including this number), or `True` (default prime factorization, currently set to 7)
- **zero\_loc** (*bool*) – Location of the zero frequency point. Can be `None` (the one with the value of f-axis closest to zero, or the first point if the frequency column is missing), `'center'` (mid-point), or an integer index.
- **symmetric\_time** (*bool*) – If `True`, make time axis go from  $(-0.5/df, 0.5/df)$  rather than  $(0, 1./df)$ .
- **raw** (*bool*) – if `True`, return a simple 1D trace with the result.

#### Returns

a two-column array, where the first column is frequency, and the second is the complex-valued trace data.

```
pylablib.core.dataproc.fourier.power_spectral_density(trace, dt=None, truncate=False,
                                                    normalization='density', single_sided=False,
                                                    window='rectangle',
                                                    window_power_compensate=True,
                                                    raw=False)
```

Calculate a power spectral density of the trace.

#### Parameters

- **trace** – Time trace to be transformed. It can be a 1D trace of values, a 2-column trace, or a 3-column trace. If *dt* is `None`, then the first column is assumed to be time (only support uniform time step), and the other columns are either the trace values (for a single data column) or real and imaginary parts of the trace (for two data columns). If *dt* is not `None`, then the time column is assumed to be missing, so the two columns are assumed to be the real and the imaginary parts.
- **dt** – if not `None`, can specify the time step between the consecutive samples; otherwise, try to get it from the time column of the trace if it exists, or set to 1 otherwise.
- **truncate** (*bool* or *int*) – Determines whether to truncate the trace to the nearest product of small primes (speeds up FFT algorithm); can be `False` (no truncation), an integer 2, 3, 5, 7, or 11 (truncate to a product of primes up to and including this number), or `True` (default prime factorization, currently set to 7)
- **normalization** (*str*) – Fourier transform normalization: - `'none'`: no (i.e., default numpy) normalization; - `'sum'`: the norm of the data is conserved ( $\text{sum}(\text{PSD}[:,1]) == \text{sum}(\text{abs}(\text{trace}[:,1])**2)$ ); - `'rms'`: sum of the PSD is equal to the RMS trace amplitude squared ( $\text{sum}(\text{PSD}[:,1]) == \text{mean}(\text{abs}(\text{trace}[:,1])**2)$ ); - `'density'`: power spectral density normalization, in  $\text{x/rHz}$  ( $\text{sum}(\text{PSD}[:,1])*df == \text{mean}(\text{abs}(\text{trace}[:,1])**2)$ ); - `'dBc'`: like `'density'`, but normalized to the mean trace value.

- **single\_sided** (*bool*) – If True, only leave positive frequency side of the PSD.
- **window** (*str*) – FT window. Can be 'rectangle' (essentially, no window), 'hann' or 'hamming'.
- **window\_power\_compensate** (*bool*) – If True, the data is multiplied by a compensating factor to preserve power in the spectrum.
- **raw** (*bool*) – if True, return a simple 1D trace with the result.

#### Returns

a two-column array, where the first column is frequency, and the second is positive PSD.

`pylablib.core.dataproc.fourier.get_real_part_ft(ft)`

Get the fourier transform of the real part only from the fourier transform of a complex variable.

`pylablib.core.dataproc.fourier.get_imag_part_ft(ft)`

Get the fourier transform of the imaginary part only from the fourier transform of a complex variable.

`pylablib.core.dataproc.fourier.get_correlations_ft(ft_a, ft_b, zero_mean=True,  
normalization='none')`

Calculate the correlation function of the two variables given their fourier transforms.

#### Parameters

- **ft\_a** – first variable fourier transform
- **ft\_b** – second variable fourier transform
- **zero\_mean** (*bool*) – If True, the value corresponding to the zero frequency is set to zero (only fluctuations around means of a and b are calculated).
- **normalization** (*str*) – Can be 'whole' (correlations are normalized by product of PSDs derived from *ft\_a* and *ft\_b*) or 'individual' (normalization is done for each frequency individually, so that the absolute value is always 1).

### pylablib.core.dataproc.iir\_transform module

Digital recursive infinite impulse response filter.

Implemented using Numba library (JIT high-performance compilation) if possible.

`pylablib.core.dataproc.iir_transform.iir_apply_complex(trace, xcoeff, ycoeff)`

Apply digital, (possibly) recursive filter with coefficients *xcoeff* and *ycoeff* along the first axis.

Result is filtered signal *y* with  $y[n] = \sum_j x[n-j] * xcoeff[j] + \sum_k y[n-k-1] * ycoeff[k]$ .

### pylablib.core.dataproc.image module

`pylablib.core.dataproc.image.convert_shape_indexing(shape, src, dst, axes=(0, 1))`

Convert image indexing style.

*shape* is the source image shape (2-tuple), *src* and *dst* are current format and desired format. Formats can be "rcb" (first index is row, second is column, rows count from the bottom), "rct" (same, but rows count from the top). "xyb" (first index is column, second is row, rows count from the bottom), or "xyt" (same but rows count from the top). "rc" is interpreted as "rct", "xy" as "xyt"



`pylablib.core.dataproc.image.convert_image_indexing(img, src, dst, axes=(0, 1))`

Convert image indexing style.

*img* is the source image (ND numpy array with  $N \geq 2$ ), *src* and *dst* are current format and desired format, *axes* specify correspondingly the row and the column axes (by default, the first two array axes). Formats can be "rcb" (first index is row, second is column, rows count from the bottom), "rct" (same, but rows count from the top), "xyb" (first index is column, second is row, rows count from the bottom), or "xyt" (same but rows count from the top). "rc" is interpreted as "rct", "xy" as "xyt"

**class** `pylablib.core.dataproc.image.ROI(imin=0, imax=None, jmin=0, jmax=None)`

Bases: `object`

**copy**()

**center**(*shape=None*)

**size**(*shape=None*)

**area**(*shape=None*)

**tup**(*shape=None*)

**ispan**(*shape=None*)

**jspan**(*shape=None*)

**classmethod** **from\_centersize**(*center, size, shape=None*)

**classmethod** **intersect**(\*args)

**limit**(*shape*)

`pylablib.core.dataproc.image.get_region(image, center, size, axis=(-2, -1))`

Get part of the image with the given center and size (both are tuples (i, j)).

The region is automatically reduced if a part of it is outside of the image.

`pylablib.core.dataproc.image.get_region_sum(image, center, size, axis=(-2, -1))`

Sum part of the image with the given center and size (both are tuples (i, j)).

The region is automatically reduced if a part of it is outside of the image. Return tuple (sum, area), where area is the actual summer region are (in pixels).

## pylablib.core.dataproc.interpolate module

`pylablib.core.dataproc.interpolate.interpolate1D_func(x, y, kind='linear', axis=-1, copy=True, bounds_error=True, fill_values=nan, assume_sorted=False)`

1D interpolation.

Simply a wrapper around `scipy.interpolate.interp1d`.

### Parameters

- **x** – 1D arrays of x coordinates for the points at which to find the values.
- **y** – array of values corresponding to x points (can have more than 1 dimension, in which case the output values are (N-1)-dimensional)
- **kind** – Interpolation method.



- **axis** – axis in y-data over which to interpolate.
- **copy** – if True, make internal copies of *x* and *y*.
- **bounds\_error** – if True, raise error if interpolation function arguments are outside of *x* bounds.
- **fill\_values** – values to fill the outside-bounds regions if **bounds\_error**==False.
- **assume\_sorted** – if True, assume that *data* is sorted.

**Returns**

A 1D array with interpolated data.

```
pylablib.core.dataproc.interpolate.interpolate1D(data, x, kind='linear', bounds_error=True,
                                                fill_values=nan, assume_sorted=False)
```

1D interpolation.

**Parameters**

- **data** – 2-column array [(*x*,*y*)], where *y* is a function of *x*.
- **x** – Arrays of *x* coordinates for the points at which to find the values.
- **kind** – Interpolation method.
- **bounds\_error** – if True, raise error if *x* values are outside of *data* bounds.
- **fill\_values** – values to fill the outside-bounds regions if **bounds\_error**==False
- **assume\_sorted** – if True, assume that *data* is sorted.

**Returns**

A 1D array with interpolated data.

```
pylablib.core.dataproc.interpolate.interpolate2D(data, x, y, method='linear', fill_value=nan)
```

Interpolate data in 2D.

Simply a wrapper around `scipy.interpolate.griddata()`.

**Parameters**

- **data** – 3-column array [(*x*,*y*,*z*)], where *z* is a function of *x* and *y*.
- **x/y** – Arrays of *x* and *y* coordinates for the points at which to find the values.
- **method** – Interpolation method.

**Returns**

A 2D array with interpolated data.

```
pylablib.core.dataproc.interpolate.interpolateND(data, xs, method='linear')
```

Interpolate data in N dimensions.

Simply a wrapper around `scipy.interpolate.griddata()`.

**Parameters**

- **data** – (N+1)-column array [(*x*<sub>1</sub>, ..., *x*<sub>N</sub>, *y*)], where *y* is a function of *x*<sub>1</sub>, ..., *x*<sub>N</sub>.
- **xs** – N-tuple of arrays of coordinates for the points at which to find the values.
- **method** – Interpolation method.

**Returns**

An ND array with interpolated data.

```
pylablib.core.dataproc.interpolate.regular_grid_from_scatter(data, x_points, y_points,  
                                                           x_range=None, y_range=None,  
                                                           method='nearest')
```

Turn irregular scatter-points data into a regular 2D grid function.

#### Parameters

- **data** – 3-column array [(x, y, z)], where z is a function of x and y.
- **x\_points/y\_points** – Number of points along x/y axes.
- **x\_range/y\_range** – If not None, a tuple specifying the desired range of the data (all points in *data* outside the range are excluded).
- **method** – Interpolation method (see `scipy.interpolate.griddata()` for options).

#### Returns

A nested tuple (*data*, (*x\_grid*, *y\_grid*)), where all entries are 2D arrays (either with data or with gridpoint locations).

```
pylablib.core.dataproc.interpolate.interpolate_trace(trace, step, rng=None, x_column=0,  
                                                    select_columns=None, kind='linear',  
                                                    assume_sorted=False)
```

Interpolate trace data over a regular grid with the given step.

*rng* specifies interpolation range (by default, whole data range). *x\_column* specifies column index for x-data. *select\_column* specifies which columns to interpolate and keep at the output (by default, all data). If *assume\_sorted*==True, assume that x-data is sorted. *kind* specifies interpolation method.

```
pylablib.core.dataproc.interpolate.average_interpolate_1D(data, step, rng=None, avg_kernel=1,  
                                                         min_weight=0, kind='linear')
```

1D interpolation combined with pre-averaging.

#### Parameters

- **data** – 2-column array [(x,y)], where y is a function of x.
- **step** – distance between the points in the interpolated data (all resulting x-coordinates are multiples of *step*).
- **rng** – if not None, specifies interpolation range (by default, whole data range).
- **avg\_kernel** – kernel used for initial averaging. Can be either a 1D array, where each point corresponds to the relative bin weight, or an integer, which specifies simple rectangular kernel of the given width.
- **min\_weight** – minimal accumulated weight in the bin to consider it ‘valid’ (if the bin is invalid, its accumulated value is ignored, and its value is obtained by the interpolation step). *min\_weight* of 0 implies any non-zero weight; otherwise, weight >= *min\_weight*.
- **kind** – Interpolation method.

#### Returns

A 2-column array with the interpolated data.

## pylablib.core.dataproc.specfunc module

Specific useful functions.

`pylablib.core.dataproc.specfunc.gaussian_k(x, sigma=1.0, height=None)`

Gaussian kernel function.

Normalized by the area if *height* is None, otherwise *height* is the value at 0.

`pylablib.core.dataproc.specfunc.rectangle_k(x, width=1.0, height=None)`

” Symmetric rectangle kernel function.

Normalized by the area if *height* is None, otherwise *height* is the value at 0.

`pylablib.core.dataproc.specfunc.lorentzian_k(x, gamma=1.0, height=None)`

Lorentzian kernel function

Normalized by the area if *height* is None, otherwise *height* is the value at 0.

`pylablib.core.dataproc.specfunc.complex_lorentzian_k(x, gamma=1.0, amplitude=1j)`

Complex Lorentzian kernel function.

`pylablib.core.dataproc.specfunc.exp_decay_k(x, width=1.0, height=None, mode='causal')`

Exponential decay kernel function

Normalized by area if *height*=None (if possible), otherwise *height* is the value at 0.

**Mode determines value for  $x < 0$ :**

- 'causal' - it's 0 for  $x < 0$ ;
- 'step' - it's constant for  $x \leq 0$ ;
- 'continue' - it's a continuous decaying exponent;
- 'mirror' - function is symmetric:  $\exp(-|x|/\text{width})$ .

`pylablib.core.dataproc.specfunc.get_kernel_func(kernel)`

Get a kernel function by its name.

Available functions are: 'gaussian', 'rectangle', 'lorentzian', 'exp\_decay', 'complex\_lorentzian'.

`pylablib.core.dataproc.specfunc.rectangle_w(x, N, ft_compensated=False)`

Rectangle FT window function

`pylablib.core.dataproc.specfunc.gen_hamming_w(x, N, alpha, beta, ft_compensated=False)`

Generalized Hamming FT window function.

If *ft\_compensated*==True, multiply the window function by a compensating factor to preserve power in the spectrum.

`pylablib.core.dataproc.specfunc.hann_w(x, N, ft_compensated=False)`

Hann FT window function.

If *ft\_compensated*==True, multiply the window function by a compensating factor to preserve power in the spectrum.

`pylablib.core.dataproc.specfunc.hamming_w(x, N, ft_compensated=False)`

Specific Hamming FT window function.

If *ft\_compensated*==True, multiply the window function by a compensating factor to preserve power in the spectrum.

`pylablib.core.dataproc.specfunc.get_window_func(window)`

Get a window function by its name.

Available functions are: 'hamming', 'rectangle', 'hann'.

`pylablib.core.dataproc.specfunc.gen_hamming_w_ft(f, t, alpha, beta)`

Get Fourier Transform of a generalized Hamming FT window function.

$f$  is the argument,  $t$  is the total window size.

`pylablib.core.dataproc.specfunc.rectangle_w_ft(f, t)`

Get Fourier Transform of the rectangle FT window function.

$f$  is the argument,  $t$  is the total window size.

`pylablib.core.dataproc.specfunc.hann_w_ft(f, t)`

Get Fourier Transform of the Hann FT window function.

$f$  is the argument,  $t$  is the total window size.

`pylablib.core.dataproc.specfunc.hamming_w_ft(f, t)`

Get Fourier Transform of the specific Hamming FT window function.

$f$  is the argument,  $t$  is the total window size.

`pylablib.core.dataproc.specfunc.get_window_ft_func(window)`

Get a Fourier Transform of a window function by its name.

Available functions are: 'hamming', 'rectangle', 'hann'.

## pylablib.core.dataproc.table\_wrap module

Utilities for uniform treatment of pandas tables and numpy arrays for functions which can deal with them both.

**class** `pylablib.core.dataproc.table_wrap.IGenWrapper(container)`

Bases: `object`

The interface for a wrapper that gives a uniform access to basic methods of wrapped objects'.

**get\_type()**

Get a string representing the wrapped object type

**copy(wrapped=False)**

Copy the object.

If `wrapped==True`, return a new wrapper containing the object copy; otherwise, just return the copy.

**ndim()**

**shape()**

**class** `pylablib.core.dataproc.table_wrap.I1DWrapper(container)`

Bases: `IGenWrapper`

A wrapper containing a 1D object (a 1D numpy array or a pandas Series object).

Provides a uniform access to basic methods of a wrapped object.

**class** `Accessor(wrapper)`

Bases: `object`

An accessor: creates a simple uniform interface to treat the wrapped object element-wise (get/set/iterate over elements).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**subcolumn**(*idx*, *wrapped=False*)

Return a subcolumn at index *idx*.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**static from\_array**(*array*, *index=None*, *force\_copy=False*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *array* (a 1D numpy array or a list).

If *force\_copy==True*, make a copy of supplied array. If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**classmethod from\_columns**(*columns*, *column\_names=None*, *index=None*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns; only length-1 lists is supported).

*column\_names* parameter is ignored. If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**array\_replaced**(*array*, *force\_copy=False*, *preserve\_index=False*, *wrapped=False*)

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in `from_array()`.

**get\_index**()

Get index of the given 1D trace, or `None` if none is available

**get\_type**()

Get a string representing the wrapped object type

**copy**(*wrapped=False*)

Copy the object.

If *wrapped==True*, return a new wrapper containing the object copy; otherwise, just return the copy.

**ndim**()

**shape**()

**class** `pylablib.core.dataproc.table_wrap.Array1DWrapper(container)`

Bases: `1DWrapper`

A wrapper for a 1D numpy array.

Provides a uniform access to basic methods of a wrapped object.

**get\_deleted**(*idx*, *wrapped=False*)

Return a copy of the column with the data at index *idx* deleted.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_inserted**(*idx, val, wrapped=False*)

Return a copy of the column with the data *val* added at index *idx*.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**insert**(*idx, val*)

Add data *val* to index *idx*

**get\_appended**(*val, wrapped=False*)

Return a copy of the column with the data *val* appended at the end.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**append**(*val*)

Append data *val* to the end

**subcolumn**(*idx, wrapped=False*)

Return a subcolumn at index *idx*.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**static from\_array**(*array, index=None, force\_copy=False, wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *array* (a 1D numpy array or a list).

If *force\_copy==True*, make a copy of supplied array. If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_type**()

Get a string representing the wrapped object type

**copy**(*wrapped=False*)

Copy the object.

If *wrapped==True*, return a new wrapper containing the object copy; otherwise, just return the copy.

**class Accessor**(*wrapper*)

Bases: `object`

An accessor: creates a simple uniform interface to treat the wrapped object element-wise (get/set/iterate over elements).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**array\_replaced**(*array, force\_copy=False, preserve\_index=False, wrapped=False*)

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in `from_array()`.

**classmethod from\_columns**(*columns, column\_names=None, index=None, wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns; only length-1 lists is supported).

*column\_names* parameter is ignored. If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_index**()

Get index of the given 1D trace, or `None` if none is available

**ndim**()

**shape()**

**class** `pylablib.core.dataproc.table_wrap.Series1DWrapper(container)`

Bases: `1DWrapper`

A wrapper for a pandas Series object.

Provides a uniform access to basic methods of a wrapped object.

**get\_deleted**(*idx*, *wrapped=False*)

Return a copy of the column with the data at index *idx* deleted.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_inserted**(*idx*, *val*, *wrapped=False*)

Return a copy of the column with the data *val* added at index *idx*.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_appended**(*val*, *wrapped=False*)

Return a copy of the column with the data *val* appended at the end.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**subcolumn**(*idx*, *wrapped=False*)

Return a subcolumn at index *idx*.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**static from\_array**(*array*, *index=None*, *force\_copy=False*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *array* (a 1D numpy array or a list).

If *force\_copy==True*, make a copy of supplied array. If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_index**()

Get index of the given 1D trace, or `None` if none is available

**get\_type**()

Get a string representing the wrapped object type

**copy**(*wrapped=False*)

Copy the object.

If *wrapped==True*, return a new wrapper containing the object copy; otherwise, just return the copy.

**class Accessor**(*wrapper*)

Bases: `object`

An accessor: creates a simple uniform interface to treat the wrapped object element-wise (get/set/iterate over elements).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**array\_replaced**(*array*, *force\_copy=False*, *preserve\_index=False*, *wrapped=False*)

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in `from_array()`.

**classmethod** `from_columns(columns, column_names=None, index=None, wrapped=False)`

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns; only length-1 lists is supported).

*column\_names* parameter is ignored. If `wrapped==True`, return a new wrapper containing the column; otherwise, just return the column.

**ndim()**

**shape()**

**class** `pylablib.core.dataproc.table_wrap.I2DWrapper(container, r=None, c=None, t=None)`

Bases: [\*IGenWrapper\*](#)

A wrapper containing a 2D object (a 2D numpy array or a pandas DataFrame object).

Provides a uniform access to basic methods of a wrapped object.

**classmethod** `from_columns(columns, column_names=None, index=None, wrapped=False)`

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns).

*column\_names* supplies names of the columns (only relevant for [\*DataFrame2DWrapper\*](#)). If `wrapped==True`, return a new wrapper containing the table; otherwise, just return the table.

**columns\_replaced(columns, preserve\_index=False, wrapped=False)**

Return copy of the object with the data replaced by *columns*.

If `wrapped==True`, return a new wrapper containing the table; otherwise, just return the table.

**static** `from_array(array, column_names=None, index=None, force_copy=False, wrapped=False)`

Build a new object of the type corresponding to the wrapper from the supplied *array* (a list of rows or a 2D numpy array).

*column\_names* supplies names of the columns (only relevant for [\*DataFrame2DWrapper\*](#)). If `wrapped==True`, return a new wrapper containing the table; otherwise, just return the table.

**array\_replaced(array, preserve\_index=None, force\_copy=False, wrapped=False)**

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in [\*from\\_array\(\)\*](#).

**get\_index()**

Get index of the given 2D table, or `None` if none is available

**get\_type()**

Get a string representing the wrapped object type

**copy(wrapped=False)**

Copy the object.

If `wrapped==True`, return a new wrapper containing the table; otherwise, just return the table.

**column(idx, wrapped=False)**

Get a column at index *idx*.

Return a 1D numpy array for a 2D numpy array object, and an Series object for a pandas DataFrame. If `wrapped==True`, return a new wrapper containing the column; otherwise, just return the column.

**subtable(idx, wrapped=False)**

Return a subtable at index *idx*.

If `wrapped==True`, return a new wrapper containing the table; otherwise, just return the table.



**ndim()**

**shape()**

**class** `pylablib.core.dataproc.table_wrap.Array2DWrapper`(*container*)

Bases: `I2DWrapper`

A wrapper for a 2D numpy array.

Provides a uniform access to basic methods of a wrapped object.

**set\_container**(*cont*)

**class** `RowAccessor`(*wrapper*, *storage*)

Bases: `object`

A row accessor: creates a simple uniform interface to treat the wrapped object row-wise (append/insert/delete/iterate over rows).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**get\_deleted**(*idx*, *wrapped=False*)

Return a new table with the rows at *idx* deleted.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**get\_inserted**(*idx*, *val*, *wrapped=False*)

Return a new table with new rows given by *val* inserted at *idx*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**insert**(*idx*, *val*)

Insert new rows given by *val* at index *idx*.

**get\_appended**(*val*, *wrapped=False*)

Return a new table with new rows given by *val* appended to the end of the table.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**append**(*val*)

Insert new rows given by *val* to the end of the table

**class** `ColumnAccessor`(*wrapper*, *storage*)

Bases: `object`

A column accessor: creates a simple uniform interface to treat the wrapped object column-wise (append/insert/delete/iterate over columns).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**get\_deleted**(*idx*, *wrapped=False*)

Return a new table with the columns at *idx* deleted.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**get\_inserted**(*idx*, *val*, *wrapped=False*)

Return a new table with new columns given by *val* inserted at *idx*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**insert**(*idx*, *val*)

Insert new columns given by *val* at index *idx*.

**get\_appended**(*val*, *wrapped=False*)

Return a new table with new columns given by *val* appended to the end of the table.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**append**(*val*)

Insert new columns given by *val* to the end of the table

**set\_names**(*names*)

Set column names (does nothing)

**get\_names**()

Get column names (all names are None)

**get\_column\_index**(*idx*)

Get number index for a given column index

**class TableAccessor**(*storage*)

Bases: `object`

A table accessor: accessing the table data through this interface returns an object of the appropriate type (numpy array for numpy wrapped object, and a DataFrame for a pandas DataFrame wrapped object).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**subtable**(*idx*, *wrapped=False*)

Return a subtable at index *idx* of the appropriate type (2D numpy array).

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**column**(*idx*, *wrapped=False*)

Get a column at index *idx* as a 1D numpy array.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**classmethod from\_columns**(*columns*, *column\_names=None*, *index=None*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns).

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table. *column\_names* parameter is ignored.

**static from\_array**(*array*, *column\_names=None*, *index=None*, *force\_copy=False*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *array* (a list of rows or a 2D numpy array).

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table. *column\_names* parameter is ignored.

**get\_type**()

Get a string representing the wrapped object type

**copy**(*wrapped=False*)

Copy the object.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**array\_replaced**(*array*, *preserve\_index=None*, *force\_copy=False*, *wrapped=False*)

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in `from_array()`.

**columns\_replaced**(*columns*, *preserve\_index=False*, *wrapped=False*)

Return copy of the object with the data replaced by *columns*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**get\_index**()

Get index of the given 2D table, or *None* if none is available

**ndim**()

**shape**()

**class** `pylablib.core.dataproc.table_wrap.DataFrame2DWrapper`(*container*)

Bases: `I2DWrapper`

A wrapper for a pandas DataFrame object.

Provides a uniform access to basic methods of a wrapped object.

**class** `RowAccessor`(*wrapper*, *storage*)

Bases: `object`

A row accessor: creates a simple uniform interface to treat the wrapped object row-wise (append/insert/delete/iterate over rows).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**get\_deleted**(*idx*, *wrapped=False*)

Return a copy of the column with the data at index *idx* deleted.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**get\_inserted**(*idx*, *val*, *wrapped=False*)

Return a new table with new rows given by *val* inserted at *idx*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**insert**(*idx*, *val*)

Insert new rows given by *val* at index *idx*.

**get\_appended**(*val*, *wrapped=False*)

Return a new table with new rows given by *val* appended to the end of the table.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**append**(*val*)

Insert new rows given by *val* to the end of the table

**class** `ColumnAccessor`(*wrapper*, *storage*)

Bases: `object`

A column accessor: creates a simple uniform interface to treat the wrapped object column-wise (append/insert/delete/iterate over columns).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**get\_deleted**(*idx*, *wrapped=False*)

Return a new table with the columns at *idx* deleted.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**get\_inserted**(*idx*, *val*, *column\_name=None*, *wrapped=False*)

Return a new table with new columns given by *val* inserted at *idx*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**insert**(*idx*, *val*, *column\_name=None*)

Insert new columns given by *val* at index *idx*

**get\_appended**(*val*, *column\_name=None*, *wrapped=False*)

Return a new table with new columns given by *val* appended to the end of the table.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**append**(*val*, *column\_name=None*)

Insert new columns given by *val* to the end of the table

**set\_names**(*names*)

Set column names

**get\_names**()

Get column names

**get\_column\_index**(*idx*)

Get number index for a given column index

**class TableAccessor**(*storage*)

Bases: `object`

A table accessor: accessing the table data through this interface returns an object of the appropriate type (numpy array for numpy wrapped object, and a DataFrame for a pandas DataFrame wrapped object).

Generated automatically for each table on creation, doesn't need to be created explicitly.

**subtable**(*idx*, *wrapped=False*)

Return a subtable at index *idx* of the appropriate type (pandas DataFrame).

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**column**(*idx*, *wrapped=False*)

Get a column at index *idx* as a pandas Series object.

If *wrapped==True*, return a new wrapper containing the column; otherwise, just return the column.

**classmethod from\_columns**(*columns*, *column\_names=None*, *index=None*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *columns* (a list of columns).

*column\_names* supplies names of the columns (only relevant for `DataFrame2DWrapper`). If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**static from\_array**(*array*, *column\_names=None*, *index=None*, *force\_copy=False*, *wrapped=False*)

Build a new object of the type corresponding to the wrapper from the supplied *array* (a list of rows or a 2D numpy array).

*column\_names* supplies names of the columns (only relevant for `DataFrame2DWrapper`). If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**get\_index**()

Get index of the given 2D table, or `None` if none is available

**get\_type**()

Get a string representing the wrapped object type

**copy**(*wrapped=False*)

Copy the object. If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table

**array\_replaced**(*array, preserve\_index=None, force\_copy=False, wrapped=False*)

Return a copy of the column with the data replaced by *array*.

All of the parameters are the same as in [from\\_array\(\)](#).

**columns\_replaced**(*columns, preserve\_index=False, wrapped=False*)

Return copy of the object with the data replaced by *columns*.

If *wrapped==True*, return a new wrapper containing the table; otherwise, just return the table.

**ndim**()

**shape**()

`pylablib.core.dataproc.table_wrap.wrap1d(container)`

Wrap a 1D container (a 1D numpy array or or a pandas Series) into an appropriate wrapper

`pylablib.core.dataproc.table_wrap.wrap2d(container)`

Wrap a 2D container (a 2D numpy array or a pandas DataFrame) into an appropriate wrapper

`pylablib.core.dataproc.table_wrap.wrap(container)`

Wrap container (a numpy array, a pandas Series or a pandas DataFrame) into an appropriate wrapper

## pylablib.core.dataproc.transform module

**class** `pylablib.core.dataproc.transform.LinearTransform`(*tmatr=None, shift=None, ndim=2*)

Bases: `object`

A generic linear transform which combines an affine transform with a given matrix and an additional shift.

### Parameters

- **tmatr** – translational matrix (if *None*, use a unity matrix)
- **shift** – added shift (if *None*, use a zero shift)
- **ndim** – if both *tmatr* and *shift* are *None*, specifies the dimensionality of the transform; otherwise, ignored

**i**(*coord, shift=True*)

**inverted**()

Return inverted transformation

**preceded**(*trans*)

Return a combined transformation which result from applying this transformation followed by *trans*

**followed**(*trans*)

Return a combined transformation which result from applying *trans* followed by this transformation

**shifted**(*shift, preceded=False*)

Return a transform with an added shift before or after (depending of *preceded*) the current one

**multiplied**(*mult*, *preceded=False*)

Return a transform with an added scaling before or after (depending of *preceded*) the current one.

*mult* can be a single number (scale), a 1D vector (scaling for each axis independently), or a matrix.

**rotated2d**(*deg*, *preceded=False*)

Return a transform with an added rotation before or after (depending of *preceded*) the current one.

Only applies to 2D transforms.

**class** pylablib.core.dataproc.transform.**Indexed2DTransform**(*tmatr=None*, *shift=None*, *rigid=False*)

Bases: [LinearTransform](#)

A restriction of [LinearTransform](#) which only applies to 2D and only allows rotations by multiples of 90 degrees.

#### Parameters

- **tmatr** – translational matrix (if *None*, use a unity matrix)
- **shift** – added shift (if *None*, use a zero shift)
- **rigid** – if *True*, only allow orthogonal transforms, i.e., no scaling

**rotated2d**(*deg*, *preceded=False*)

Return a transform with an added rotation before or after (depending of *preceded*) the current one.

Only applies to 2D transforms.

**followed**(*trans*)

Return a combined transformation which result from applying *trans* followed by this transformation

**i**(*coord*, *shift=True*)

**inverted**()

Return inverted transformation

**multiplied**(*mult*, *preceded=False*)

Return a transform with an added scaling before or after (depending of *preceded*) the current one.

*mult* can be a single number (scale), a 1D vector (scaling for each axis independently), or a matrix.

**preceded**(*trans*)

Return a combined transformation which result from applying this transformation followed by *trans*

**shifted**(*shift*, *preceded=False*)

Return a transform with an added shift before or after (depending of *preceded*) the current one

## pylablib.core.dataproc.utils module

Generic utilities for dealing with numerical arrays.

**pylablib.core.dataproc.utils.is\_ascending**(*trace*)

Check the if the trace is ascending.

If it has more than 1 dimension, check all lines along 0'th axis.

**pylablib.core.dataproc.utils.is\_descending**(*trace*)

Check if the trace is descending.

If it has more than 1 dimension, check all lines along 0'th axis.

`pylablib.core.dataproc.utils.is_ordered(trace)`

Check if the trace is ordered (ascending or descending).

If it has more than 1 dimension, check all lines along 0'th axis.

`pylablib.core.dataproc.utils.is_linear(trace)`

Check if the trace is linear (values go with a constant step).

If it has more than 1 dimension, check all lines along 0'th axis (with the same step for all).

`pylablib.core.dataproc.utils.get_x_column(t, x_column=None, idx_default=False)`

Get x column of the table.

***x\_column* can be**

- an array: return as is;
- '#': return index array;
- None: equivalent to '#' for 1D data if `idx_default==False`, or to 0 otherwise;
- integer: return the column with this index.

`pylablib.core.dataproc.utils.get_y_column(t, y_column=None)`

Get y column of the table.

***y\_column* can be**

- an array: return as is;
- '#': return index array;
- None: return *t* for 1D data, or the column 1 otherwise;
- integer: return the column with this index.

`pylablib.core.dataproc.utils.sort_by(t, x_column=None, reverse=False, stable=False)`

Sort a table using selected column as a key and preserving rows.

If `reverse==True`, sort in descending order. *x\_column* values are described in [get\\_x\\_column\(\)](#). If `stable==True`, use stable sort (could be slower and uses more memory, but preserves the order of elements for the same key)

`pylablib.core.dataproc.utils.filter_by(t, columns=None, pred=None, exclude=False)`

Filter 1D or 2D array using a predicate.

If the data is 2D, *columns* contains indices of columns to be passed to the *pred* function. If `exclude==False`, drop all of the rows satisfying *pred* rather than keep them.

`pylablib.core.dataproc.utils.unique_slices(t, u_column)`

Split a table into subtables with different values in a given column.

Return a list of *t* subtables, each of which has a different (and equal among all rows in the subtable) value in *u\_column*.

`pylablib.core.dataproc.utils.merge(ts, idx=None, as_array=True)`

Merge several tables column-wise.

If *idx* is not None, then it is a list of index columns (one column per table) used for merging. The rows that have the same value in the index columns are merged; if some values aren't contained in all the *ts*, the corresponding rows are omitted. If *idx* is None, just join the tables together (they must have the same number of rows).

If `as_array==True`, return a simple numpy array as a result; otherwise, return a pandas DataFrame if applicable (note that in this case all column names in all tables must be different to avoid conflicts)

**class** pylablib.core.dataproc.utils.**Range**(*start=None, stop=None*)

Bases: [object](#)

Single data range.

If *start* or *stop* are *None*, it's implied that they're at infinity (i.e., `Range(None, None)` is infinite). If the range object is *None*, it's implied that the range is empty

**property** *start*

**property** *stop*

**contains**(*x*)

Check if *x* is in the range

**intersect**(*\*rngs*)

Find an intersection of multiple ranges.

If the intersection is empty, return *None*.

**rescale**(*mult=1.0, shift=0.0*)

**tup**()

**pylablib.core.dataproc.utils.find\_closest\_arg**(*xs, x, approach='both', ordered=False*)

Find the index of a value in *xs* that is closest to *x*.

*approach* can take values 'top', 'bottom' or 'both' and denotes from which side should array elements approach *x* (meaning that the found array element should be  $>x$ ,  $<x$  or just the closest one). If there are no elements lying on the desired side of *x* (e.g. `approach=='top'` and all elements of *xs* are less than *x*), the function returns *None*. if `ordered==True`, then *xs* is assumed to be in ascending or descending order, and binary search is implemented (works only for 1D arrays). if there are recurring elements, return any of them.

**pylablib.core.dataproc.utils.find\_closest\_value**(*xs, x, approach='both', ordered=False*)

**pylablib.core.dataproc.utils.get\_range\_indices**(*xs, xs\_range, ordered=False*)

Find trace indices corresponding to the given range.

The range is defined as `xs_range[0]:xs_range[1]`, or infinite if `xs_range=None` (so the data is returned unchanged in that case). If `ordered==True`, then the function assumes that *xs* in ascending or descending order.

**pylablib.core.dataproc.utils.cut\_to\_range**(*t, xs\_range, x\_column=None, ordered=False*)

Cut the table to the given range based on *x\_column*.

The range is defined as `xs_range[0]:xs_range[1]`, or infinite if `xs_range=None`. *x\_column* is used to determine which column's values to use to check if the point is in range (see [get\\_x\\_column\(\)](#)). If `ordered_x==True`, then the function assumes that *x\_column* in ascending order.

**pylablib.core.dataproc.utils.cut\_out\_regions**(*t, regions, x\_column=None, ordered=False, multi\_pass=True*)

Cut the regions out of the *t* based on *x\_column*.

*x\_column* is used to determine which column's values to use to check if the point is in range (see [get\\_x\\_column\(\)](#)). If `ordered_x==True`, then the function assumes that *x\_column* in ascending order. If `multi_pass==False`, combine all indices before deleting the data in a single operation (works faster, but only for non-intersecting regions).



`pylablib.core.dataproc.utils.find_discrete_step(trace, min_fraction=1e-08, tolerance=1e-05)`

Try to find a minimal divisor of all steps in a 1D trace.

*min\_fraction* is the minimal possible size of the divisor (relative to the minimal non-zero step size). *tolerance* is the tolerance of the division. Raise an `ArithmeticError` if no such value was found.

`pylablib.core.dataproc.utils.unwrap_mod_data(trace, wrap_range)`

Unwrap data given *wrap\_range*.

Assume that every jump greater than  $0.5 * \text{wrap\_range}$  is not real and is due to value being restricted. Can be used to, e.g., unwrap the phase data.

`pylablib.core.dataproc.utils.pad_trace(trace, pad, mode='constant', cval=0.0)`

Expand 1D trace or a multi-column table for different convolution techniques.

Wrapper around `numpy.pad()`, but can handle pandas dataframes or multi-column arrays. Note that the index data is not preserved.

#### Parameters

- **trace** – 1D array-like object.
- **pad** (*int* or *tuple*) – Expansion size. Can be an integer, if pad on both sides is equal, or a 2-tuple (*left*, *right*) for pads on opposite sides.
- **mode** (*str*) – Expansion mode. Takes the same values as `numpy.pad()`. Common values are 'constant' (added values are determined by *cval*), 'edge' (added values are end values of the trace), 'reflect' (reflect trace with respect to its endpoint) or 'wrap' (wrap the values from the other size).
- **cval** (*float*) – If mode=='constant', determines the expanded values.

`pylablib.core.dataproc.utils.xy2c(t)`

Convert a trace or a table from xy representation to a single complex data.

*t* is a 2D array with either 2 columns (x and y) or 3 columns (index, x and y). Return 2D array with either 1 column (c) or 2 columns (index and c).

`pylablib.core.dataproc.utils.c2xy(t)`

Convert the a trace or a table from complex representation to a split x and y data.

*t* is either 1D array (c data) or a 2D array with either 1 column (c) or 2 columns (index and c). Return 2D array with either 2 column (x and y) or 3 columns (index, x and y).

## Module contents

### pylablib.core.devio package

#### Submodules

#### pylablib.core.devio.SCPi module

```
class pylablib.core.devio.SCPi.SCPIDevice(conn, term_write=None, term_read=None,
                                          wait_callback=None, backend='auto',
                                          backend_defaults=None, failsafe=None, timeout=None,
                                          backend_params=None)
```

Bases: *ICommBackendWrapper*

A base class for a device controlled with the usual SCPI syntax.

**Implements two functions:**

- deals with composing and parsing of standard SCPI commands and simplifying repetitive property access routines
- implements automatic re-sending and reconnecting on communication failures (fail-safe mode)

**Parameters**

- **conn** – Connection parameters (depend on the backend). Can also be an opened *comm\_backend.IDeviceCommBackend* class for a custom backend.
- **term\_write** (*str*) – Line terminator for writing operations.
- **wait\_callback** (*callable*) – A function to be called periodically (every 300ms by default) while waiting for operations to complete.
- **backend** (*str*) – Connection backend (e.g., 'serial' or 'visa').
- **backend\_defaults** – if not None, specifies a dictionary {backend: params} with default connection parameters (depending on the backend), which are added to *conn*
- **failsafe** (*bool*) – If True, the device is working in a fail-safe mode: if an operation times out, attempt to repeat it several times before raising error. If None, use the class value *\_default\_failsafe* (False by default).
- **timeout** (*float*) – Default timeout (in seconds).

**Error**

alias of *DeviceError*

**ReraiseError** = None

**BackendError**

alias of *DeviceBackendError*

**reconnect** (*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**sleep** (*delay*)

Wait for *delay* seconds

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive *write()* operations are bundled together with ; delimiter. The actual write is performed at the *read()/ask()* operation or at the end of the block.

**get\_id** (*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**reset**()

Reset the device (by default, "\*RST" command)

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**static get\_arg\_type**(*arg*)

Autodetect argument type

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as

True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**class NoParameterCaller**(*device, kind*)

Bases: `object`

Class to simplify calling functions without a parameter

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: b'##', then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

## pylablib.core.devio.backend\_logger module

**class** `pylablib.core.devio.backend_logger.BackendLogger`(*path*)

Bases: `object`

Backend logger.

Receives log requests from backends and stores them in a predefined file.

### Parameters

**path** – path to save the log

**start**(*header*)

Start logging section

**stop**()

Stop logging section

**section**(*header*)

Context manager for operations within a header

**log**(*operation, value*)

Log the operation

`pylablib.core.devio.backend_logger.load_logfile`(*path*)

Load backend log file.

Return a list of tuples [(*header*, *section*)], where *header* is the header name, and *section* is the list [(*op*, *value*)] with operations ("r", "w", or "e") and corresponding values.

## pylablib.core.devio.base module

**exception** pylablib.core.devio.base.**DeviceError**

Bases: [RuntimeError](#)

Generic device communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## pylablib.core.devio.comm\_backend module

Routines for defining a unified interface across multiple backends.

**exception** pylablib.core.devio.comm\_backend.**DeviceBackendError**(*exc*)

Bases: [DeviceError](#)

Generic exception relaying a backend error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.core.devio.comm\_backend.reraise**(*func*)

Wrapper for a backend method which intercepts backend exceptions and re-emits them as a subclass of [DeviceBackendError](#) defined in the class

**pylablib.core.devio.comm\_backend.logerror**(*func*)

Wrapper for a backend method which logs if any errors escaped

**class** pylablib.core.devio.comm\_backend.**IDeviceCommBackend**(*conn*, *timeout=None*, *term\_write=None*,  
*term\_read=None*, *datatype='auto'*,  
*reraise\_error=None*)

Bases: [object](#)

An abstract class for a device communication backend.

Connection is automatically opened on creation.

### Parameters

- **conn** – Connection parameters (depend on the backend).
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations.
- **term\_read** (*str*) – Line terminator for reading operations.

- **datatype** (*str*) – Type of the returned data; can be "bytes" (return bytes object), "str" (return str object), or "auto" (default Python result: str in Python 2 and bytes in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of *DeviceBackendError*.

**BackendError = None**

Base class for the errors raised by the backend operations

**Error**

alias of *DeviceBackendError*

**classmethod combine\_conn(conn1, conn2)**

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**classmethod get\_backend\_name()**

Get string representation of the backend (e.g., "serial", "visa", or "network")

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**setup\_cooldown(\*\*kwargs)**

Setup cooldown times for various operations.

The arguments are of the form *kind=value*, where *value* is the cooldown time (in seconds), and *kind* is the operation kind (common kinds are *open*, *close*, *read*, *write*, *timeout*, and *flush*). *kind* can also be *default* (default value for all kind), or *all* (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by *\_default\_operation\_cooldown* class attribute dictionary.

**cooldown(kind='default')**

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are *open*, *close*, *read*, *write*, *timeout*, and *flush*); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**set\_timeout(timeout)**

Set operations timeout (in seconds)

**get\_timeout()**

Get operations timeout (in seconds)

**using\_timeout**(*timeout=None*)

Context manager for usage of a different timeout inside a block

**readline**(*remove\_term=True, timeout=None, skip\_empty=True*)

Read a single line from the device.

**Parameters**

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).

**readlines**(*lines\_num, remove\_term=True, timeout=None, skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**read**(*size=None*)

Read data from the device.

If *size* is not None, read *size* bytes (the standard timeout applies); otherwise, read all available data (return immediately).

**flush\_read**()

Flush the device output (read all the available data; return the number of bytes read)

**write**(*data, flush=True, read\_echo=False, read\_echo\_delay=0, read\_echo\_lines=1*)

Write data to the device.

If `flush==True`, flush the write buffer. If `read_echo==True`, wait for *read\_echo\_delay* seconds and then perform [readline\(\)](#) (*read\_echo\_lines* times).

**ask**(*query, delay=0.0, read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If `read_all==True`, read all the available data; otherwise, read a single line.

**static list\_resources**(*desc=False*)

List all available resources for this backend.

If `desc==False`, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

`pylablib.core.devio.comm_backend.remove_longest_term(msg, terms)`

Remove the longest terminator among *terms* from the end of the message.

**exception** `pylablib.core.devio.comm_backend.DeviceVisaError`(*exc*)

Bases: [DeviceBackendError](#)

Visa backend operation error

**add\_note**()

`Exception.add_note(note)` – add a note to the exception

**args**



**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

```
class pylablib.core.devio.comm_backend.VisaDeviceBackend(conn, timeout=10.0, term_write=None,
                                                         term_read=None, do_lock=None,
                                                         datatype='auto', reraise_error=None)
```

Bases: [IDeviceCommBackend](#)

NIVisa backend (via pyVISA).

Connection is automatically opened on creation.

**Parameters**

- **conn** (*str*) – Connection string.
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – Line terminator for reading operations (specifies when [readline\(\)](#) stops).
- **do\_lock** (*bool*) – If True, employ locking operations; otherwise, locking function does nothing.
- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of [DeviceBackendError](#).

**BackendError**

Base class for the errors raised by the backend operations

alias of [object](#)

**Error**

alias of [DeviceVisaError](#)

```
static list_resources(desc=False)
```

List all available resources for this backend.

If desc==False, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

```
lock(timeout=None)
```

Lock the access to the device from other threads/processes

**unlock()**

Unlock the access to the device from other threads/processes

**locking**(*timeout=None*)

Context manager for lock & unlock

**set\_timeout**(*timeout*)

Set operations timeout (in seconds)

**get\_timeout**()

Get operations timeout (in seconds)

**readline**(*remove\_term=True, timeout=None, skip\_empty=True*)

Read a single line from the device.

#### Parameters

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).

**read**(*size=None*)

Read data from the device.

If *size* is not None, read *size* bytes (the standard timeout applies); otherwise, read all available data (return immediately).

**write**(*data, flush=True, read\_echo=False, read\_echo\_delay=0, read\_echo\_lines=1*)

Write data to the device.

If `read_echo==True`, wait for *read\_echo\_delay* seconds and then perform `readline()` (*read\_echo\_lines* times). *flush* parameter is ignored.

**ask**(*query, delay=0.0, read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If `read_all==True`, read all the available data; otherwise, read a single line.

**classmethod combine\_conn**(*conn1, conn2*)

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown**(*kind='default'*)

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read**()

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name**()

Get string representation of the backend (e.g., "serial", "visa", or "network")

**readlines**(*lines\_num, remove\_term=True, timeout=None, skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in `readline()`.

**setup\_cooldown(\*\*kwargs)**

Setup cooldown times for various operations.

The arguments are of the form `kind=value`, where `value` is the cooldown time (in seconds), and `kind` is the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`). `kind` can also be `default` (default value for all kind), or `all` (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by `_default_operation_cooldown` class attribute dictionary.

**using\_timeout(timeout=None)**

Context manager for usage of a different timeout inside a block

**exception** `pylablib.core.devio.comm_backend.DeviceSerialError(exc)`

Bases: [`DeviceBackendError`](#)

Serial backend operation error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

```
class pylablib.core.devio.comm_backend.SerialDeviceBackend(conn, timeout=10.0, term_write=None,
                                                         term_read=None,
                                                         connect_on_operation=False,
                                                         open_retry_times=3, no_dtrrts=False,
                                                         datatype='auto', reraise_error=None)
```

Bases: [`IDeviceCommBackend`](#)

Serial backend (via pySerial).

Connection is automatically opened on creation.

#### Parameters

- **conn** – Connection parameters. Can be either a string (for a port), or a list/tuple (`port`, `baudrate`, `bytesize`, `parity`, `stopbits`, `xonxoff`, `rtscts`, `dsrdr`) supplied to the serial connection (default is `('COM1', 19200, 8, 'N', 1, 0, 0, 0)`), or a dict with the same parameters.
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – List of possible single-char terminator for reading operations (specifies when [`readline\(\)`](#) stops).
- **connect\_on\_operation** (*bool*) – If `True`, the connection is normally closed, and is opened only on the operations (normally two processes can't be simultaneously connected to the same device).
- **open\_retry\_times** (*int*) – Number of times the connection is attempted before giving up.
- **no\_dtrrts** (*bool*) – If `True`, turn off DTR and RTS status lines before opening (e.g., turns off reset-on-connection for Arduino controllers).

- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of *DeviceBackendError*.

**BackendError**

Base class for the errors raised by the backend operations

alias of *object*

**Error**

alias of *DeviceSerialError*

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**single\_op()**

Context manager for a single operation.

If `connect_on_operation==True` during creation, wrapping several command in *single\_op* prevents the connection from being closed and reopened between the operations (only opened in the beginning and closed in the end).

**set\_timeout(timeout)**

Set operations timeout (in seconds)

**get\_timeout()**

Get operations timeout (in seconds)

**readline(remove\_term=True, timeout=None, skip\_empty=True, error\_on\_timeout=True)**

Read a single line from the device.

**Parameters**

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**read(size=None)**

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

**read\_multichar\_term(term, remove\_term=True, timeout=None, error\_on\_timeout=True)**

Read a single line with multiple possible terminators.

**Parameters**

- **term** – Either a string (single multi-char terminator) or a list of strings (multiple terminators).
- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**write**(*data*, *flush=True*, *read\_echo=False*, *read\_echo\_delay=0*, *read\_echo\_lines=1*)

Write data to the device.

If *flush==True*, flush the write buffer. If *read\_echo==True*, wait for *read\_echo\_delay* seconds and then perform [readline\(\)](#) (*read\_echo\_lines* times).

**static list\_resources**(*desc=False*)

List all available resources for this backend.

If *desc==False*, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

**ask**(*query*, *delay=0.0*, *read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If *read\_all==True*, read all the available data; otherwise, read a single line.

**classmethod combine\_conn**(*conn1*, *conn2*)

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown**(*kind='default'*)

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read**()

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name**()

Get string representation of the backend (e.g., "serial", "visa", or "network")

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**readlines**(*lines\_num*, *remove\_term=True*, *timeout=None*, *skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**setup\_cooldown**(*\*\*kwargs*)

Setup cooldown times for various operations.

The arguments are of the form `kind=value`, where *value* is the cooldown time (in seconds), and *kind* is the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`). *kind* can also be `default` (default value for all kind), or `all` (reset all cooldown values to this value). The

cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by `_default_operation_cooldown` class attribute dictionary.

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_timeout**(*timeout=None*)

Context manager for usage of a different timeout inside a block

**exception** `pylablib.core.devio.comm_backend.DeviceFT232Error`(*exc*)

Bases: [`DeviceBackendError`](#)

FT232 backend operation error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.core.devio.comm_backend.FT232DeviceBackend`(*conn, timeout=10.0, term\_write=None, term\_read=None, open\_retry\_times=3, datatype='auto', reraise\_error=None*)

Bases: [`IDeviceCommBackend`](#)

FT232 backend (via pyft232).

Connection is automatically opened on creation.

#### Parameters

- **conn** – Connection parameters. Can be either a string (for a port), or a list/tuple (`port`, `baudrate`, `bytesize`, `parity`, `stopbits`, `xonxoff`, `rtscts`) supplied to the serial connection (default is ('COM1', 19200, 8, 'N', 1, 0, 0, 0)), or a dict with the same parameters.
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – List of possible single-char terminator for reading operations (specifies when [`readline\(\)`](#) stops).
- **open\_retry\_times** (*int*) – Number of times the connection is attempted before giving up.
- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not *None*, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of [`DeviceBackendError`](#).

#### BackendError

Base class for the errors raised by the backend operations

alias of [`object`](#)

**Error**

alias of *DeviceFT232Error*

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**single\_op()**

Context manager for a single operation.

Does nothing.

**set\_timeout(timeout)**

Set operations timeout (in seconds)

**get\_timeout()**

Get operations timeout (in seconds)

**readline(remove\_term=True, timeout=None, skip\_empty=True, error\_on\_timeout=True)**

Read a single line from the device.

**Parameters**

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**read(size=None)**

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

**read\_multichar\_term(term, remove\_term=True, timeout=None, error\_on\_timeout=True)**

Read a single line with multiple possible terminators.

**Parameters**

- **term** – Either a string (single multi-char terminator) or a list of strings (multiple terminators).
- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**write**(*data*, *flush=True*, *read\_echo=False*, *read\_echo\_delay=0*, *read\_echo\_lines=1*)

Write data to the device.

If *flush==True*, flush the write buffer. If *read\_echo==True*, wait for *read\_echo\_delay* seconds and then perform [readline\(\)](#) (*read\_echo\_lines* times).

**static list\_resources**(*desc=False*)

List all available resources for this backend.

If *desc==False*, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns *None*.

**ask**(*query*, *delay=0.0*, *read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If *read\_all==True*, read all the available data; otherwise, read a single line.

**classmethod combine\_conn**(*conn1*, *conn2*)

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown**(*kind='default'*)

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are *open*, *close*, *read*, *write*, *timeout*, and *flush*); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read**()

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name**()

Get string representation of the backend (e.g., "serial", "visa", or "network")

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**readlines**(*lines\_num*, *remove\_term=True*, *timeout=None*, *skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**setup\_cooldown**(*\*\*kwargs*)

Setup cooldown times for various operations.

The arguments are of the form *kind=value*, where *value* is the cooldown time (in seconds), and *kind* is the operation kind (common kinds are *open*, *close*, *read*, *write*, *timeout*, and *flush*). *kind* can also be *default* (default value for all kind), or *all* (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by `_default_operation_cooldown` class attribute dictionary.

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)



**using\_timeout**(*timeout=None*)

Context manager for usage of a different timeout inside a block

**exception** `pylablib.core.devio.comm_backend.DeviceNetworkError`(*exc*)

Bases: [DeviceBackendError](#)

Network backend operation error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.core.devio.comm_backend.NetworkDeviceBackend`(*conn, timeout=10.0, term\_write=None, term\_read=None, datatype='auto', reraise\_error=None*)

Bases: [IDeviceCommBackend](#)

Serial backend (via pySerial).

Connection is automatically opened on creation.

#### Parameters

- **conn** – Connection parameters. Can be either a string "IP:port" (e.g., "127.0.0.1:80"), or a tuple (IP,port), where *IP* is a string and *port* is a number.
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – List of possible single-char terminator for reading operations (specifies when [readline\(\)](#) stops).
- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of [DeviceBackendError](#).

---

**Note:** If *term\_read* is a string, its behavior is different from the VISA backend: instead of being a multi-char terminator it is assumed to be a set of single-char terminators. If multi-char terminator is required, *term\_read* should be a single-element list instead of a string.

---

#### BackendError

Base class for the errors raised by the backend operations

alias of [OSError](#)

#### Error

alias of [DeviceNetworkError](#)

**open**()

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**set\_timeout(timeout)**

Set operations timeout (in seconds)

**get\_timeout()**

Get operations timeout (in seconds)

**readline(remove\_term=True, timeout=None, skip\_empty=True)**

Read a single line from the device.

#### Parameters

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).

**read(size=None)**

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

**read\_multichar\_term(term, remove\_term=True, timeout=None)**

Read a single line with multiple possible terminators.

#### Parameters

- **term** – Either a string (single multi-char terminator) or a list of strings (multiple terminators).
- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.

**write(data, flush=True, read\_echo=False, read\_echo\_delay=0, read\_echo\_lines=1)**

Write data to the device.

If `read_echo==True`, wait for *read\_echo\_delay* seconds and then perform `readline()` (*read\_echo\_lines* times). *flush* parameter is ignored.

**ask(query, delay=0.0, read\_all=False)**

Perform a write followed by a read, with *delay* in between.

If `read_all==True`, read all the available data; otherwise, read a single line.

**classmethod combine\_conn(conn1, conn2)**

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown(kind='default')**

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read()**

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name()**

Get string representation of the backend (e.g., "serial", "visa", or "network")

**static list\_resources(desc=False)**

List all available resources for this backend.

If desc==False, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**readlines(lines\_num, remove\_term=True, timeout=None, skip\_empty=True)**

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**setup\_cooldown(\*\*kwargs)**

Setup cooldown times for various operations.

The arguments are of the form kind=value, where value is the cooldown time (in seconds), and kind is the operation kind (common kinds are open, close, read, write, timeout, and flush). kind can also be default (default value for all kind), or all (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by \_default\_operation\_cooldown class attribute dictionary.

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_timeout(timeout=None)**

Context manager for usage of a different timeout inside a block

**exception pylablib.core.devio.comm\_backend.DeviceUSBError(exc)**

Bases: [DeviceBackendError](#)

USB backend operation error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

```
class pylablib.core.devio.comm_backend.PyUSBDeviceBackend(conn, timeout=10.0, term_write=None,
                                                         term_read=None,
                                                         check_read_size=True, datatype='auto',
                                                         reraise_error=None)
```

Bases: *IDeviceCommBackend*

USB backend (via PyUSB package).

Connection is automatically opened on creation.

#### Parameters

- **conn** – Connection parameters. Can be either a string (for a port), or a list/tuple (vendorID, productID, index, endpoint\_read, endpoint\_write, backend) supplied to the connection (default is (0x0000, 0x0000, 0, 0x00, 0x01, 'libusb1'), which is invalid for most devices), or a dict with the same parameters. vendorID and productID specify device kind, index is an integer index (starting from zero) of the device among several identical (i.e., with the same ids) ones, and endpoint\_read and endpoint\_write specify connection endpoints for the specific device.
- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – List of possible single-char terminator for reading operations (specifies when *readline()* stops).
- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of *DeviceBackendError*.

#### BackendError

Base class for the errors raised by the backend operations

alias of *USBError*

#### Error

alias of *DeviceUSBError*

#### open()

Open the connection

#### close()

Close the connection

#### is\_opened()

Check if the device is connected

#### set\_timeout(timeout)

Set operations timeout (in seconds)

#### get\_timeout()

Get operations timeout (in seconds)

#### readline(remove\_term=True, timeout=None, skip\_empty=True, error\_on\_timeout=True)

Read a single line from the device.

#### Parameters

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.

- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**read**(*size=None, max\_read\_size=65536*)

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

**read\_multichar\_term**(*term, remove\_term=True, timeout=None, error\_on\_timeout=True*)

Read a single line with multiple possible terminators.

#### Parameters

- **term** – Either a string (single multi-char terminator) or a list of strings (multiple terminators).
- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**write**(*data, flush=True, read\_echo=False, read\_echo\_delay=0, read\_echo\_lines=1*)

Write data to the device.

If `read_echo==True`, wait for *read\_echo\_delay* seconds and then perform `readline()` (*read\_echo\_lines* times). *flush* parameter is ignored.

**static list\_resources**(*desc=False, \*\*kwargs*)

List all available resources for this backend.

If `desc==False`, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

**ask**(*query, delay=0.0, read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If `read_all==True`, read all the available data; otherwise, read a single line.

**classmethod combine\_conn**(*conn1, conn2*)

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown**(*kind='default'*)

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read**()

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name**()

Get string representation of the backend (e.g., "serial", "visa", or "network")

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**readlines**(*lines\_num, remove\_term=True, timeout=None, skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**setup\_cooldown**(*\*\*kwargs*)

Setup cooldown times for various operations.

The arguments are of the form `kind=value`, where `value` is the cooldown time (in seconds), and `kind` is the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`). `kind` can also be `default` (default value for all kind), or `all` (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by `_default_operation_cooldown` class attribute dictionary.

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_timeout**(*timeout=None*)

Context manager for usage of a different timeout inside a block

**exception** `pylablib.core.devio.comm_backend.DeviceHIDError`(*exc*)

Bases: [DeviceBackendError](#)

HID backend operation error

**add\_note**()

`Exception.add_note(note)` – add a note to the exception

**args**

**with\_traceback**()

`Exception.with_traceback(tb)` – set `self.__traceback__` to `tb` and return `self`.

**class** `pylablib.core.devio.comm_backend.HIDDeviceBackend`(*conn, timeout=10.0, term\_write=None, term\_read=None, datatype='auto', reraise\_error=None*)

Bases: [IDeviceCommBackend](#)

HID backend (via Windows DLLs).

Connection is automatically opened on creation.

#### Parameters

- **conn** – Connection parameters. Can be either a string (for a port), or a list/tuple (`vendorID`, `productID`, `index`, `endpoint_read`, `endpoint_write`, `backend`) supplied to the connection (default is `(0x0000, 0x0000, 0, 0x00, 0x01, 'libusb1')`, which is invalid for most devices), or a dict with the same parameters. `vendorID` and `productID` specify device kind, `index` is an integer index (starting from zero) of the device among several identical (i.e., with the same ids) ones, and `endpoint_read` and `endpoint_write` specify connection endpoints for the specific device.

- **timeout** (*float*) – Default timeout (in seconds).
- **term\_write** (*str*) – Line terminator for writing operations; appended to the data
- **term\_read** (*str*) – List of possible single-char terminator for reading operations (specifies when *readline()* stops).
- **datatype** (*str*) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not None, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of *DeviceBackendError*.

### BackendError

Base class for the errors raised by the backend operations

alias of *HIDError*

### Error

alias of *DeviceHIDError*

### open()

Open the connection

### close()

Close the connection

### is\_opened()

Check if the device is connected

### set\_timeout(timeout)

Set operations timeout (in seconds)

### get\_timeout()

Get operations timeout (in seconds)

### readline(remove\_term=True, timeout=None, skip\_empty=True, error\_on\_timeout=True)

Read a single line from the device.

#### Parameters

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

### read(size=None)

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

### read\_multichar\_term(term, remove\_term=True, timeout=None, error\_on\_timeout=True)

Read a single line with multiple possible terminators.

#### Parameters

- **term** – Either a string (single multi-char terminator) or a list of strings (multiple terminators).
- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **error\_on\_timeout** (*bool*) – If False, return an incomplete line instead of raising the error on timeout.

**get\_pending()**

Get the number of bytes in the read buffer

**write**(*data*, *flush=True*, *read\_echo=False*, *read\_echo\_delay=0*, *read\_echo\_lines=1*)

Write data to the device.

If *read\_echo==True*, wait for *read\_echo\_delay* seconds and then perform [readline\(\)](#) (*read\_echo\_lines* times). *flush* parameter is ignored.

**static list\_resources**(*desc=False*, *\*\*kwargs*)

List all available resources for this backend.

If *desc==False*, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns None.

**ask**(*query*, *delay=0.0*, *read\_all=False*)

Perform a write followed by a read, with *delay* in between.

If *read\_all==True*, read all the available data; otherwise, read a single line.

**classmethod combine\_conn**(*conn1*, *conn2*)

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown**(*kind='default'*)

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read()**

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name()**

Get string representation of the backend (e.g., "serial", "visa", or "network")

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**readlines**(*lines\_num*, *remove\_term=True*, *timeout=None*, *skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).



**setup\_cooldown(\*\*kwargs)**

Setup cooldown times for various operations.

The arguments are of the form `kind=value`, where `value` is the cooldown time (in seconds), and `kind` is the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`). `kind` can also be `default` (default value for all kind), or `all` (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by `_default_operation_cooldown` class attribute dictionary.

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_timeout(timeout=None)**

Context manager for usage of a different timeout inside a block

**exception** `pylablib.core.devio.comm_backend.DeviceRecordedError(exc)`

Bases: [\*DeviceBackendError\*](#)

Recorded backend operation error

**add\_note()**

`Exception.add_note(note)` – add a note to the exception

**args****with\_traceback()**

`Exception.with_traceback(tb)` – set `self.__traceback__` to `tb` and return `self`.

**class** `pylablib.core.devio.comm_backend.RecordedDeviceBackend(conn, datatype='auto', reraise_error=None)`

Bases: [\*IDeviceCommBackend\*](#)

Recorded backend.

Connection is automatically opened on creation.

**Parameters**

- **conn** – connection parameters (recorded log path)
- **datatype** (*str*) – Type of the returned data; can be `"bytes"` (return *bytes* object), `"str"` (return *str* object), or `"auto"` (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **reraise\_error** – if not `None`, specifies an error to be re-raised on any backend exception (by default, use backend-specific error); should be a subclass of [\*DeviceBackendError\*](#).

**BackendError**

alias of [\*OSError\*](#)

**Error**

alias of [\*DeviceRecordedError\*](#)

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**start(header)**

Start recorded section

**stop()**

Stop logging section

**section(header)**

**readline(remove\_term=True, timeout=None, skip\_empty=True)**

Read a single line from the device.

**Parameters**

- **remove\_term** (*bool*) – If True, remove terminal characters from the result.
- **timeout** – Operation timeout. If None, use the default device timeout.
- **skip\_empty** (*bool*) – If True, ignore empty lines (works only for `remove_term==True`).

**read(size=None)**

Read data from the device.

If *size* is not None, read *size* bytes (usual timeout applies); otherwise, read all available data (return immediately).

**write(data, flush=True, read\_echo=False, read\_echo\_delay=0, read\_echo\_lines=1)**

Write data to the device.

If `flush==True`, flush the write buffer. If `read_echo==True`, wait for *read\_echo\_delay* seconds and then perform [readline\(\)](#) (*read\_echo\_lines* times).

**ask(query, delay=0.0, read\_all=False)**

Perform a write followed by a read, with *delay* in between.

If `read_all==True`, read all the available data; otherwise, read a single line.

**classmethod combine\_conn(conn1, conn2)**

Combined two connection parameters into a single dictionary (*conn1* overrides *conn2*)

**cooldown(kind='default')**

Cooldown between the operations.

*kind* specifies the operation kind (common kinds are `open`, `close`, `read`, `write`, `timeout`, and `flush`); "default" corresponds to the default cooldown (usually, specified as 0). Called automatically by various backend operations, so usually there is no need to call explicitly.

**flush\_read()**

Flush the device output (read all the available data; return the number of bytes read)

**classmethod get\_backend\_name()**

Get string representation of the backend (e.g., "serial", "visa", or "network")

**get\_timeout()**

Get operations timeout (in seconds)

**static list\_resources**(*desc=False*)

List all available resources for this backend.

If *desc==False*, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

Might not be implemented (depending on the backend), in which case returns *None*.

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**readlines**(*lines\_num, remove\_term=True, timeout=None, skip\_empty=True*)

Read multiple lines from the device.

Parameters are the same as in [readline\(\)](#).

**set\_timeout**(*timeout*)

Set operations timeout (in seconds)

**setup\_cooldown**(*\*\*kwargs*)

Setup cooldown times for various operations.

The arguments are of the form *kind=value*, where *value* is the cooldown time (in seconds), and *kind* is the operation kind (common kinds are *open*, *close*, *read*, *write*, *timeout*, and *flush*). *kind* can also be *default* (default value for all kind), or *all* (reset all cooldown values to this value). The cooldowns of the given kinds are usually called after the corresponding operation (it is necessary for some devices, otherwise the communication can freeze or crush). Default cooldown values are specified by *\_default\_operation\_cooldown* class attribute dictionary.

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_timeout**(*timeout=None*)

Context manager for usage of a different timeout inside a block

`pylablib.core.devio.comm_backend.autodetect_backend(conn, default='visa')`

Try to determine the backend by the connection.

*default* specifies the default backend which is returned if the backend is unclear.

`pylablib.core.devio.comm_backend.new_backend(conn, backend='auto', defaults=None, **kwargs)`

Build new backend with the supplied parameters.

#### Parameters

- **conn** – Connection parameters (depend on the backend). Can be simply connection parameters (tuple or dict) for the given backend (e.g., "192.168.0.1" or ("COM1", 19200)), a tuple (*backend*, *conn*) which specifies both backend and connection (in which case it overrides the supplied backend), or an already opened backend (in which case it is returned as is)
- **backend** (*str*) – Backend type. Available backends are 'auto' (try to autodetect based on the connection), 'visa', 'serial', 'ft232', 'network', and 'pyusb'. Can also be directly a backend class (more appropriate for custom backends), or a tuple ('auto', *backend*), which is analogous to 'auto', but it returns the specified backend if the autodetection fails; by default, the fallback backend is 'visa', so 'auto' is exactly the same as ('auto', 'visa').

- **defaults** – if not None, specifies a dictionary {**backend**: **params**} with default connection parameters (depending on the backend), which are added to the connection parameters
- **\*\*kwargs** – parameters sent to the backend.

`pylablib.core.devio.comm_backend.backend_error(backend, conn=None)`

Return error class corresponding to the current backend.

Like `new_backend()`, allows setting `backend="auto"`, in which case `conn` is used to try and autodetect the backend kind (not completely reliable, should be avoided).

`pylablib.core.devio.comm_backend.list_backend_resources(backend=None, desc=False)`

List all resources for the given backend.

If `backend` is None, return dictionary {**backend**: **resources**} for all available backends. If `desc==False`, return list of connections (usually strings or tuples), which can be used to connect to the device. Otherwise, return a list of descriptions, which have more info, but can be backend-dependent.

**class** `pylablib.core.devio.comm_backend.ICommBackendWrapper(instr)`

Bases: `IDevice`

A base class for an instrument using a communication backend.

#### Parameters

**instr** – Backend (assumed to be already opened).

**apply\_settings(settings)**

Apply the settings.

`settings` is the dict {**name**: **value**} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {**name**: **value**} containing full device information (including status and settings).

`include` specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {**name**: **value**} containing the device status (including settings).

`include` specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings(include=0)**

Get dict {**name**: **value**} containing all the device settings.

`include` specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**open()**

Open the backend

**close()**

Close the backend

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

## pylablib.core.devio.data\_format module

Library for binary data encoding/decoding for device communication and dealing with different data format representations in different contexts (numpy, SCPI, etc.).

**class** `pylablib.core.devio.data_format.DataFormat`(*size, kind, byteorder*)

Bases: `object`

Describes data encoding for device communications.

### Parameters

- **size** (*int*) – Size of a single element (in bytes).
- **kind** (*str*) – Kind of the element. Can be 'i' (integer), 'u' (unsigned integer), 'f' (floating point) or 'ascii' (text representation).
- **byteorder** (*str*) – Byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

**flip\_byteorder()**

Flip byteorder of the description

**is\_ascii()**

Check of the format is textual

**static from\_desc**(*desc, str\_type='numpy'*)

Build the format from the string description.

*str\_type* is the description format. Can be 'numpy' (numpy dtype description), 'struct' (`struct` description) or 'SCPI' (the standard SCPI description).

**static from\_desc\_SCPI**(*desc, border='norm'*)

Build the format from the string SCPI description.

*border* describes byte order (either 'norm' or 'swap').

**to\_desc**(*str\_type='auto'*)

Build a description string of this format.

*str\_type* can be 'auto' (similar to 'numpy', but also accepts 'ascii'), 'numpy', 'struct' or 'SCPI' (return tuple (*desc*, *border*)).

**convert\_from\_str**(data)

Convert the string data into an array

**convert\_to\_str**(data, ascii\_format='.5f')

Convert the array into a string data.

ascii\_format is the `str.format()` string for textual representation.

## pylablib.core.devio.hid module

**class** pylablib.core.devio.hid.**TDeviceDescription**(path, manufacturer, product, serial, vendor\_id, product\_id, version)

Bases: `tuple`

**manufacturer**

**path**

**product**

**product\_id**

**serial**

**vendor\_id**

**version**

**pylablib.core.devio.hid.list\_devices()**

List HID devices.

Return list of tuples (path, manufacturer, product, serial, vendor\_id, product\_id, version), where path is the string path used for connection.

**class** pylablib.core.devio.hid.**HIDevice**(path, timeout=3.0, rep\_fmt='lenpfx', pause\_on\_write=True)

Bases: `object`

Generic HID-based device interface.

### Parameters

- **path** – HID path (usually obtained using `hid.list_devices()`)
- **timeout** – communication timeout
- **rep\_fmt** – HID report format; can be "raw" (read/write raw data from/to HID), "lenpfx" (assume a format where the first byte for the report indicates the payload size), or a tuple (parser, builder) of two functions, where the `parser` takes a single raw report data argument and returns a parsed value, while `builder` takes 2 arguments (data to be written and the output report size) and return the bytes to be sent to HID.
- **pause\_on\_write** – if True, pause the reading loop when writing; makes some communications more stable

**open()**

Open the device connection if it is not opened yet

**close()**

Close the device connection

**is\_opened()**

Check if the device connection is opened

**get\_description()**

Get device description

Return tuple (path, manufacturer, product, serial, vendor\_id, product\_id, version), where path is the string path used for connection.

**get\_timeout()**

Get device communication timeout

**set\_timeout(timeout)**

Set device communication timeout

**class Reader(f, caps, bufsize, parser)**

Bases: `object`

**loop\_read()****start\_loop()**

Start the read loop

**stop\_loop()**

Stop the read loop

**pausing(do\_pause=True, timeout=None)****read(nbytes=None, timeout=None, peek=False)**

Read the given number of bytes from the read buffer.

If *nbytes* is `None`, return all read bytes. If *timeout* is not `None`, it can define the read operation timeout; otherwise, use the default timeout specified on creation. If *peek*==`True`, return the bytes but keep them in the buffer.

**get\_pending()**

Get the number of bytes in the read buffer

**get\_pending()**

Get the number of bytes in the read buffer

**read(nbytes=None, timeout=None)**

Read the given number of bytes from the read buffer.

If *nbytes* is `None`, return all read bytes. If *timeout* is not `None`, it can define the read operation timeout; otherwise, use the default timeout specified on creation.

**write(data, timeout=None)**

Write the given data to the device.

If *timeout* is not `None`, it can define the write operation timeout; otherwise, use the default timeout specified on creation.

**pylablib.core.devio.hid\_base module****exception** `pylablib.core.devio.hid_base.HIDError`Bases: `RuntimeError`

Generic HID error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.devio.hid_base.HIDLibError(func, code)`Bases: `HIDError`

Generic HID library boolean function error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.devio.hid_base.HIDTimeoutError`Bases: `HIDError`

HID read timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.core.devio.interface module****class** `pylablib.core.devio.interface.IDevice`Bases: `object`

A base class for an instrument.

Contains some useful functions for dealing with device settings.

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected



**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**class pylablib.core.devio.interface.IParameterClass(name)**

Bases: `object`

A generic parameter class.

Deals with converting device interface representation and the ‘internal’ representation (e.g., names used in SCPI commands or integer indices). Also responsible for validating the user-passed and device-returned parameters.

Needs to define to methods: `__call__` for converting user parameters (‘alias’) into the device parameters (‘value’) and `i()` for the opposite conversion. In addition, it provides `using_device()` context manager to temporarily change the device attribute, which can be used by some parameter classes for device-dependent conversions.

**Parameters**

**name** – parameter class name; used to match method arguments with corresponding classes.

**using\_device(device)**

Context manager for temporarily changing the device attribute to the given device instance

**docstring()**

Get a parameter docstring

**i(value, device=None)**

Convert device parameter value into a corresponding use parameter value

If not None, *device* specifies the corresponding device instance for device-dependent conversion.

**class** pylablib.core.devio.interface.**ICheckingParameterClass**(*name*)

Bases: *IPParameterClass*

Parameter class which separately handles checking and conversion.

Specifies six methods: *check\_value()*, *to\_alias()* and *\_value\_error\_str* for handling value-to-alias conversion, and *check\_alias()*, *to\_value()* and *\_alias\_error\_str* for handling alias-to-value conversion.

**check\_alias**(*alias*)

Check if the alias is valid

**check\_value**(*value*)

Check if the device value is valid

**to\_value**(*alias*)

Convert the alias into a device value

**to\_alias**(*value*)

Convert the device value into an alias

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**docstring**()

Get a parameter docstring

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

**class** pylablib.core.devio.interface.**RangeParameterClass**(*name*, *minval=None*, *maxval=None*,  
*out\_of\_range='error'*)

Bases: *ICheckingParameterClass*

Parameter class for numerical values constrained to a certain range.

#### Parameters

- **name** – parameter class name
- **minval** – minimal allowed value (inclusive); *None* means no lower limit
- **maxval** – maximal allowed value (inclusive); *None* means no upper limit
- **out\_of\_range** – action if an out-of-range value is supplied; can be either "error" (raise an error), or "truncate" (truncate to the nearest limit).

**check\_value**(*value*)

Check if the device value is valid

**check\_alias**(*alias*)

Check if the alias is valid

**to\_value**(*alias*)

Convert the alias into a device value

**docstring**()

Get a parameter docstring

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**to\_alias**(*value*)

Convert the device value into an alias

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

```
class pylablib.core.devio.interface.IEnumParameterClass(name, allowed_alias='device_values',
                                                         allowed_value='exact', alias_case=None,
                                                         value_case=None, match_prefix=False)
```

Bases: *ICheckingParameterClass*

Parameter class for a generic enum (i.e., predefined values) parameter.

**Defines two methods for handling conversion:**

- **\_get\_value\_map** which returns a dictionary for converting device values into aliases,
- **\_get\_alias\_map** which returns a dictionary for converting aliases into device values.

These methods need to be redefined in subclasses.

#### Parameters

- **name** – parameter class name
- **allowed\_alias** – specifies a range of allowed aliases; can be "exact" (only exact map matches are allowed), "device\_value" (exact map matches and raw device values are allowed), or "all" (all values are allowed); in the latter two cases the value not in the map are passed as is.
- **allowed\_value** – specifies a range of allowed device values; can be "exact" (only exact map matches are allowed), or "all" (all values are allowed); in the latter case the value not in the map is passed as is.
- **alias\_case** – default alias parameter case for string values; can be *None* (no case normalization), or "lower" or "upper" (any received or returned alias will be normalized into this case)
- **value\_case** – default value parameter case for string values; can be *None* (no case normalization), or "lower" or "upper" (any received or returned device value will be normalized into this case)
- **match\_prefix** – if *True*, then the keys in the value map (returned by **\_get\_value\_map** method) are interpreted as prefixes, so in the value-to-alias conversion the converted value matches the map value if it just starts with it; in the case of ambiguity (several map values are prefixes for the same converted value), the exact match takes priority; useful for some SCPI devices, where the shorter version of the value can sometimes be returned.

**check\_value**(*value*)

Check if the device value is valid

**check\_alias**(*alias*)

Check if the alias is valid

**to\_value**(*alias*)

Convert the alias into a device value

**to\_alias**(*value*)

Convert the device value into an alias

**docstring**()

Get a parameter docstring

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

```
class pylablib.core.devio.interface.EnumParameterClass(name, alias_map, value_map=None,
                                                         allowed_alias='device_values',
                                                         allowed_value='exact', alias_case=None,
                                                         value_case=None, match_prefix=False)
```

Bases: *IEnumParameterClass*

Parameter class for a enum (i.e., predefined values) parameter with the specified mapping.

#### Parameters

- **name** – parameter class name
- **alias\_map** – mapping of aliases to device values; can be a dictionary, or a list of (*alias*, *value*) tuples (in the latter case non-tuple values are also allowed, indicating that value is the same as the alias); the list representation is useful in cases where the same alias maps to more than one value, so the map inversion is impossible
- **value\_map** – mapping of device values to aliases; can only be a dictionary or *None*, which means that the alias map is automatically inverted
- **allowed\_alias** – specifies a range of allowed aliases; can be "exact" (only exact map matches are allowed), "device\_value" (exact map matches and raw device values are allowed), or "all" (all values are allowed); in the latter two cases the value not in the map are passed as is.
- **allowed\_value** – specifies a range of allowed device values; can be "exact" (only exact map matches are allowed), or "all" (all values are allowed); in the latter case the value not in the map is passed as is.
- **alias\_case** – default alias parameter case for string values; can be *None* (no case normalization), or "lower" or "upper" (any received or returned alias will be normalized into this case)
- **value\_case** – default value parameter case for string values; can be *None* (no case normalization), or "lower" or "upper" (any received or returned device value will be normalized into this case)
- **match\_prefix** – if *True*, then the keys in the value map (or values in the alias map, if only it is provided) are assumed to be prefixes, so in the value-to-alias conversion the converted value matches the map value if it just starts with it; useful for some SCPI devices, where the shorter version of the value can sometimes be returned.

**check\_alias**(*alias*)

Check if the alias is valid

**check\_value**(*value*)

Check if the device value is valid

**docstring**()

Get a parameter docstring

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**to\_alias**(*value*)

Convert the device value into an alias

**to\_value**(*alias*)

Convert the alias into a device value

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

**class** pylablib.core.devio.interface.**FunctionParameterClass**(*name*, *to\_alias=None*, *to\_value=None*, *check\_value=None*, *check\_alias=None*, *alias\_err=None*, *value\_err=None*)

Bases: [\*ICheckingParameterClass\*](#)

Parameter class which uses supplied methods for checking, conversion, and generating error messages.

The arguments correspond to the parameter methods with the same names. When not supplied, checking methods always return *True*, conversion methods leave value intact, and error string methods generate the default error messages.

**check\_value**(*value*)

Check if the device value is valid

**check\_alias**(*alias*)

Check if the alias is valid

**to\_alias**(*value*)

Convert the device value into an alias

**to\_value**(*alias*)

Convert the alias into a device value

**docstring**()

Get a parameter docstring

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

**class** pylablib.core.devio.interface.**CombinedParameterClass**(*name*, *parameters*)

Bases: [\*IPParameterClass\*](#)

A multi-stage combined parameter class, which performs several conversion/check stages.

**Parameters**

- **name** – parameter class name
- **parameters** – list of parameters classes which are combined; the order is from the ‘most alias’ to the ‘most device parameter’, i.e., when converting an alias to a device parameter, it is first passed to the first class, then the second, etc. (the reverse is done when converting device values into aliases)

**docstring()**

Get a parameter docstring

**i**(*value*, *device=None*)

Convert device parameter value into a corresponding use parameter value

If not *None*, *device* specifies the corresponding device instance for device-dependent conversion.

**using\_device**(*device*)

Context manager for temporarily changing the device attribute to the given device instance

**class** pylablib.core.devio.interface.**TRawParameterValue**(*value*)

Bases: `tuple`

**value**

`pylablib.core.devio.interface.pval`(*value*)

Mark that the value has already been treated by the parameter class

`pylablib.core.devio.interface.use_parameters`(\**args*, \*\**kwargs*)

Wrapper to indicate that a device class method uses device parameter classes.

The corresponding parameters classes are automatically determined if the argument name matches the parameter class name. The parameters classes can also be defined explicitly using keywords arguments `arg=parameter` supplied to the wrapper, where `arg` is the argument, and `parameter` is either a parameter class instance, or a parameter class name (the more preferable way). In addition, an argument `_returns` can be used to define the parameter class for the return value; it can also be a list or a tuple of parameter classes, indicating that the returned value is also a list or a tuple.

## Module contents

### pylablib.core.fileio package

#### Submodules

#### pylablib.core.fileio.datafile module

**class** pylablib.core.fileio.datafile.**DataFile**(*data*, *filepath=None*, *filetype=None*, *creation\_time=None*, *comments=None*, *props=None*)

Bases: `object`

Describes a single datafile.

**Parameters**

- **data** – the main content of the file (usually a numpy array, a pandas DataFrame or a `Dictionary`).
- **filepath** (*str*) – absolute path from which the file was read
- **filetype** (*str*) – a source type (e.g., "csv" or "bin")

- **creation\_time** (*datetime.datetime*) – File creation time
- **props** (*dict*) – all the metainfo about the file (extracted from comments, filename etc.)
- **comments** (*list*) – all the comments excluding the ones containing props

**get**(*name*, *default=None*)

Get a property from the dictionary. Use default value if it's not found

## pylablib.core.fileio.dict\_entry module

Classes for dealing with the *Dictionary* entries with special conversion rules when saved or loaded. Used to redefine how certain objects (e.g., tables) inside dictionaries are written into files and read from files.

**pylablib.core.fileio.dict\_entry.is\_dict\_entry\_branch**(*branch*)

Check if the dictionary branch contains a dictionary entry which needs to be specially converted.

**class** **pylablib.core.fileio.dict\_entry.DictEntryBuilder**(*entry\_cls*, *pred=None*, *\*\*kwargs*)

Bases: *object*

Object for building dictionary entries from objects.

### Parameters

- **entry\_cls** – dictionary entry class
- **pred** – method used to check if an object can be turned into the corresponding entry; if *None*, use the default entry class checker (*entry\_class.is\_data\_valid*)
- **kwargs** – keyword arguments passed to the entry constructor along with the data

**is\_data\_valid**(*data*)

Check if a data object can be wrapped by the current entry class

**from\_data**(*data*)

Build a dictionary entry from the data

**class** **pylablib.core.fileio.dict\_entry.DictEntryParser**(*entry\_cls*, *pred=None*, *\*\*kwargs*)

Bases: *object*

Object for building dictionary entries from dictionary branches.

### Parameters

- **entry\_cls** – dictionary entry class
- **pred** – method used to check if a dictionary branch can be turned into the corresponding entry; if *None*, use the default entry class checker (*entry\_class.is\_branch\_valid*)
- **kwargs** – keyword arguments passed to the entry *from\_dict* class method along with the branch

**is\_branch\_valid**(*branch*)

Check if a branch can be parsed by the current entry class

**from\_dict**(*dict\_ptr*, *loc*)

Build a dictionary entry from the branch and the file location

**pylablib.core.fileio.dict\_entry.add\_dict\_entry\_builder**(*builder*)

Add an entry builder to the global list of builders

`pylablib.core.fileio.dict_entry.add_dict_entry_parser(parser)`

Add an entry parser to the global list of parsers

`pylablib.core.fileio.dict_entry.add_dict_entry_class(cls)`

Add an entry class.

Automatically registers builder and parser, which take no additional arguments and use default class method to determine if an object/branch can be converted into an entry.

`pylablib.core.fileio.dict_entry.from_data(data, builders=None)`

Build a dictionary entry from the data.

*builders* can contain an additional list of builder to try before using the default ones.

`pylablib.core.fileio.dict_entry.from_dict(dict_ptr, loc, parsers=None)`

Build a dictionary entry from the dictionary branch and the file location.

*parsers* can contain an additional list of parsers to try before using the default ones.

**class** `pylablib.core.fileio.dict_entry.IDictionaryEntry(data)`

Bases: `object`

A generic *Dictionary* entry.

Contains data represented by the node, as well as the way to represent this data as a dictionary branch.

#### Parameters

**data** – data to be wrapped

**classmethod** `is_data_valid(data)`

Check if a data object can be wrapped by the current entry class

**classmethod** `is_branch_valid(branch)`

Check if a branch can be parsed by the current entry class

**classmethod** `from_dict(dict_ptr, loc)`

Convert a dictionary branch to a specific *IDictionaryEntry* object.

#### Parameters

- **dict\_ptr** (`dictionary.DictionaryPointer`) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.

**to\_dict**(*dict\_ptr, loc*)

Convert data to a dictionary branch on saving.

#### Parameters

- **dict\_ptr** (`dictionary.DictionaryPointer`) – Pointer to the dictionary location for the entry.
- **loc** – File location for the data to be saved.

`pylablib.core.fileio.dict_entry.parse_stored_table_data(desc=None, data=None, out_type='pandas')`

Parse table data corresponding to the given description dictionary and data.

#### Parameters

- **desc** – description dictionary; can be None, if no description is given



- **data** – separately loaded data; can be `None`, if no data is given (in this case assume that it is stored in the description dictionary); can be a tuple (`column_data`, `column_names`) (such as the one returned by `parse_csv.read_table()`), or a an `InlineTable` object containing such tuple.
- **out\_type** (`str`) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects).

**Returns**

tuple (`data`, `columns`), where `data` is the data table in the specified format, and `columns` is the list of columns

**class** `pylablib.core.fileio.dict_entry.ITableDictionaryEntry(data, columns=None)`

Bases: `IDictionaryEntry`

A generic table Dictionary entry.

**Parameters**

- **data** – Table data.
- **columns** (`list`) – If not `None`, list of column names (if `None` and data is a pandas DataFrame object, get column names from that).

**classmethod** `is_data_valid(data)`

Check if a data object can be wrapped by the current entry class

**classmethod** `from_dict(dict_ptr, loc, out_type='pandas')`

Convert a dictionary branch to a specific DictionaryEntry object.

**Parameters**

- **dict\_ptr** (`dictionary.DictionaryPointer`) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.
- **out\_type** (`str`) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects), used only if the dictionary doesn't provide the format.

**classmethod** `is_branch_valid(branch)`

Check if a branch can be parsed by the current entry class

**to\_dict** (`dict_ptr, loc`)

Convert data to a dictionary branch on saving.

**Parameters**

- **dict\_ptr** (`dictionary.DictionaryPointer`) – Pointer to the dictionary location for the entry.
- **loc** – File location for the data to be saved.

**class** `pylablib.core.fileio.dict_entry.InlineTableDictionaryEntry(data, columns=None)`

Bases: `ITableDictionaryEntry`

An inlined table Dictionary entry.

**Parameters**

- **data** – Table data.
- **columns** (`list`) – If not `None`, a list of column names (if `None` and data is a pandas DataFrame object, get column names from that).

**to\_dict**(*dict\_ptr*, *loc*)

Convert the data to a dictionary branch and write the table to the file.

**classmethod from\_dict**(*dict\_ptr*, *loc*, *out\_type*='pandas')

Build an *InlineTableDictionaryEntry* object from the dictionary and read the inlined data.

**Parameters**

- **dict\_ptr** (*dictionary.DictionaryPointer*) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.
- **out\_type** (*str*) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects).

**classmethod is\_branch\_valid**(*branch*)

Check if a branch can be parsed by the current entry class

**classmethod is\_data\_valid**(*data*)

Check if a data object can be wrapped by the current entry class

**class** pylablib.core.fileio.dict\_entry.**IExternalTableDictionaryEntry**(*data*, *file\_format*, *name*,  
*columns*,  
*force\_name*=True)

Bases: *ITableDictionaryEntry*

**classmethod from\_dict**(*dict\_ptr*, *loc*, *out\_type*='pandas')

Convert a dictionary branch to a specific DictionaryEntry object.

**Parameters**

- **dict\_ptr** (*dictionary.DictionaryPointer*) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.
- **out\_type** (*str*) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects), used only if the dictionary doesn't provide the format.

**classmethod is\_branch\_valid**(*branch*)

Check if a branch can be parsed by the current entry class

**classmethod is\_data\_valid**(*data*)

Check if a data object can be wrapped by the current entry class

**to\_dict**(*dict\_ptr*, *loc*)

Convert data to a dictionary branch on saving.

**Parameters**

- **dict\_ptr** (*dictionary.DictionaryPointer*) – Pointer to the dictionary location for the entry.
- **loc** – File location for the data to be saved.

**class** pylablib.core.fileio.dict\_entry.**ExternalTextTableDictionaryEntry**(*data*=None,  
*file\_format*='csv',  
*name*="",  
*columns*=None,  
*force\_name*=True)

Bases: [\*IExternalTableDictionaryEntry\*](#)

An external text table Dictionary entry.

#### Parameters

- **data** – Table data.
- **file\_format** (*str*) – Output file format.
- **name** (*str*) – Name template for the external file (default is the full path connected with "\_" symbol).
- **columns** (*list*) – If not `None`, a list of column names (if `None` and data is a pandas DataFrame object, get column names from that).
- **force\_name** (*bool*) – If `False` and the target file already exists, generate a new unique name; otherwise, overwrite the file.

**to\_dict**(*dict\_ptr*, *loc*)

Convert the data to a dictionary branch and save the table to an external file.

**classmethod from\_dict**(*dict\_ptr*, *loc*, *out\_type*='pandas')

Build an [\*ExternalTextTableDictionaryEntry\*](#) object from the dictionary and load the external data.

#### Parameters

- **dict\_ptr** ([\*dictionary.DictionaryPointer\*](#)) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.
- **out\_type** (*str*) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects).

**classmethod is\_branch\_valid**(*branch*)

Check if a branch can be parsed by the current entry class

**classmethod is\_data\_valid**(*data*)

Check if a data object can be wrapped by the current entry class

```
class pylablib.core.fileio.dict_entry.ExternalBinTableDictionaryEntry(data=None,
                                                                    file_format='bin',
                                                                    name="", columns=None,
                                                                    force_name=True)
```

Bases: [\*IExternalTableDictionaryEntry\*](#)

An external binary table Dictionary entry.

#### Parameters

- **data** – Table data.
- **file\_format** (*str*) – Output file format.
- **name** (*str*) – Name template for the external file (default is the full path connected with "\_" symbol).
- **columns** (*list*) – If not `None`, a list of column names (if `None` and data is a pandas DataFrame object, get column names from that).
- **force\_name** (*bool*) – If `False` and the target file already exists, generate a new unique name; otherwise, overwrite the file.

**to\_dict**(*dict\_ptr*, *loc*)

Convert the data to a dictionary branch and save the table to an external file.

**classmethod from\_dict**(*dict\_ptr*, *loc*, *out\_type*='pandas')

Build an [\*ExternalBinTableDictionaryEntry\*](#) object from the dictionary and load the external data.

**Parameters**

- **dict\_ptr** ([\*dictionary.DictionaryPointer\*](#)) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.
- **out\_type** (*str*) – Output format of the data ('array' for numpy arrays or 'pandas' for pandas DataFrame objects).

**classmethod is\_branch\_valid**(*branch*)

Check if a branch can be parsed by the current entry class

**classmethod is\_data\_valid**(*data*)

Check if a data object can be wrapped by the current entry class

`pylablib.core.fileio.dict_entry.table_entry_builder`(*table\_format*='inline')

Make an entry builder for tables depending on the table format.

**Parameters**

**table\_format** (*str*) – Default format for table (numpy arrays or pandas DataFrames) entries. Can be 'inline' (table is written inside the file), 'csv' (external CSV file) or 'bin' (external binary file).

**class** `pylablib.core.fileio.dict_entry.IExternalFileDictionaryEntry`(*data*, *name*="",  
force\_name=True)

Bases: [\*IDictionaryEntry\*](#)

Generic dictionary entry for data in an external file.

**Parameters**

- **data** – Stored data.
- **name** (*str*) – Name template for the external file (default is the full path connected with "\_" symbol).
- **force\_name** (*bool*) – If False and the target file already exists, generate a new unique name; otherwise, overwrite the file.

**file\_format** = None

**static add\_file\_format**(*subclass*)

Register an [\*IExternalFileDictionaryEntry\*](#) as a possible stored file format.

Used to automatically invoke a correct loader when loading the dictionary file. Only needs to be done once after the subclass declaration.

**to\_dict**(*dict\_ptr*, *loc*)

Convert the data to a dictionary branch and save the data to an external file

**classmethod from\_dict**(*dict\_ptr*, *loc*)

Build an [\*IExternalFileDictionaryEntry\*](#) object from the dictionary and load the external data.

**Parameters**

- **dict\_ptr** ([dictionary.DictionaryPointer](#)) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.

**get\_preamble()**

Generate preamble (dictionary with supplementary data which allows to load the data from the file)

**save\_file(location\_file)**

Save stored data into the given location.

Virtual method, should be overloaded in subclasses

**classmethod load\_file(location\_file, preamble)**

Load stored data from the given location, using the supplied preamble.

Virtual method, should be overloaded in subclasses

**classmethod is\_branch\_valid(branch)**

Check if a branch can be parsed by the current entry class

**classmethod is\_data\_valid(data)**

Check if a data object can be wrapped by the current entry class

```
class pylablib.core.fileio.dict_entry.ExternalNumpyDictionaryEntry(data, name="",
                                                                    force_name=True,
                                                                    dtype=None)
```

Bases: [IExternalFileDictionaryEntry](#)

A dictionary entry which stores the numpy array data into an external file in binary format.

**Parameters**

- **data** – Numpy array data.
- **name** (*str*) – Name template for the external file (default is the full path connected with "\_" symbol).
- **force\_name** (*bool*) – If False and the target file already exists, generate a new unique name; otherwise, overwrite the file.
- **dtype** – numpy dtype to load/save the data (by default, dtype of the supplied data).

```
file_format = 'numpy'
```

**get\_preamble()**

Generate preamble (dictionary with supplementary data which allows to load the data from the file)

**save\_file(location\_file)**

Save stored data into the given location

**classmethod load\_file(location\_file, preamble)**

Load stored data from the given location, using the supplied preamble

**static add\_file\_format(subclass)**

Register an [IExternalFileDictionaryEntry](#) as a possible stored file format.

Used to automatically invoke a correct loader when loading the dictionary file. Only needs to be done once after the subclass declaration.

**classmethod** `from_dict(dict_ptr, loc)`

Build an [IExternalFileDictionaryEntry](#) object from the dictionary and load the external data.

**Parameters**

- **dict\_ptr** ([dictionary.DictionaryPointer](#)) – Pointer to the dictionary location for the entry.
- **loc** – Location for the data to be loaded.

**classmethod** `is_branch_valid(branch)`

Check if a branch can be parsed by the current entry class

**classmethod** `is_data_valid(data)`

Check if a data object can be wrapped by the current entry class

**to\_dict(dict\_ptr, loc)**

Convert the data to a dictionary branch and save the data to an external file

**class** `pylablib.core.fileio.dict_entry.ExpandedContainerDictionaryEntry(data)`

Bases: [IDictionaryEntry](#)

A dictionary entry which expands containers (lists, tuples, dictionaries) into subdictionaries.

Useful when the data in the containers is complex, so writing it into one line (as is default for lists and tuples) wouldn't work.

**Parameters**

**data** – Container data.

**to\_dict(dict\_ptr, loc)**

Convert the stored container to a dictionary branch

**classmethod** `from_dict(dict_ptr, loc)`

Build an [ExpandedContainerDictionaryEntry](#) object from the dictionary

**classmethod** `is_branch_valid(branch)`

Check if a branch can be parsed by the current entry class

**classmethod** `is_data_valid(data)`

Check if a data object can be wrapped by the current entry class

## **pylablib.core.fileio.loadfile module**

Utilities for reading data files.

**class** `pylablib.core.fileio.loadfile.IInputFileFormat`

Bases: [object](#)

Generic class for an input file format.

Based on *file\_format* or autodetection, calls one of its subclasses to read the file.

Defines a single static method

**static** `detect_file_format(location_file)`

**read(location\_file)**

Read a file at a given location

```
class pylablib.core.fileio.loadfile.ITextInputFileFormat
```

Bases: [\*IInputFileFormat\*](#)

Generic class for a text input file format.

Based on *file\_format* or autodetection, calls one of its subclasses to read the file.

```
static detect_file_format(location_file)
```

```
read(location_file)
```

Read a file at a given location

```
class pylablib.core.fileio.loadfile.CSVTableInputFileFormat(out_type='default', dtype='numeric',
                                                             columns=None, delimiters=None,
                                                             empty_entry_substitute=None,
                                                             ignore_corrupted_lines=True,
                                                             skip_lines=0)
```

Bases: [\*ITextInputFileFormat\*](#)

Class for CSV input file format.

#### Parameters

- **out\_type** (*str*) – type of the result: 'array' for numpy array, 'pandas' for pandas DataFrame, or 'default' (determined by the library default; 'pandas' by default)
- **dtype** – dtype of entries; can be either a single type, or a list of types (one per column). Possible dtypes are: 'int', 'float', 'complex', 'numeric' (tries to coerce to minimal possible numeric type, raises error if data can't be converted to *complex*), 'generic' (accept arbitrary types, including lists, dictionaries, escaped strings, etc.), 'raw' (keep raw string).
- **columns** – either a number if columns, or a list of columns names.
- **delimiters** (*str*) – Regex string which recognizes entries delimiters (by default `r"\s*,\s*|\s+"`, i.e., commas and whitespaces).
- **empty\_entry\_substitute** – Substitute for empty table entries. If None, all empty table entries are skipped.
- **ignore\_corrupted\_lines** (*bool*) – If True, skip corrupted (e.g., non-numeric for numeric dtype, or with too few entries) lines; otherwise, raise [\*ValueError\*](#).
- **skip\_lines** (*int*) – Number of lines to skip from the beginning of the file.

```
read(location_file)
```

Read a file at a given location

```
static detect_file_format(location_file)
```

```
class pylablib.core.fileio.loadfile.DictionaryInputFileFormat(case_normalization=None,
                                                                inline_dtype='generic',
                                                                inline_out_type='default',
                                                                entry_format='value',
                                                                allow_duplicate_keys=False,
                                                                skip_lines=0)
```

Bases: [\*ITextInputFileFormat\*](#)

Class for Dictionary input file format.

#### Parameters

- **location\_file** – Location of the data.
- **case\_normalization** (*str*) – If *None*, the dictionary paths are case-sensitive; otherwise, defines the way the entries are normalized ('lower' or 'upper').
- **inline\_dtype** (*str*) – dtype for inlined tables.
- **inline\_out\_type** (*str*) – type of the result of the inline table: 'array' for numpy array, 'pandas' for pandas DataFrame, 'raw' for raw [InlineTable](#) data containing tuple (column\_data, column\_names), or 'default' (determined by the library default; 'pandas' by default).
- **entry\_format** (*str*) – Determines the way for dealing with [dict\\_entry.IDictionaryEntry](#) objects (objects transformed into dictionary branches with special recognition rules). Can be 'branch' (don't attempt to recognize those object, leave dictionary as in the file), 'dict\_entry' (recognize and leave as [dict\\_entry.IDictionaryEntry](#) objects) or 'value' (recognize and keep the value).
- **allow\_duplicate\_keys** (*bool*) – if *False* and the same key is mentioned twice in the file, raise an error
- **skip\_lines** (*int*) – Number of lines to skip from the beginning of the file.

**read**(*location\_file*)

Read a file at a given location

**static detect\_file\_format**(*location\_file*)

```
class pylablib.core.fileio.loadfile.BinaryTableInputFileFormatter(out_type='default',
                                                                    dtype='<f8', columns=None,
                                                                    packing='flatten',
                                                                    preamble=None,
                                                                    skip_bytes=0)
```

Bases: [IInputFileFormat](#)

Class for binary input file format.

#### Parameters

- **location\_file** – Location of the data.
- **out\_type** (*str*) – type of the result: 'array' for numpy array, 'pandas' for pandas DataFrame, or 'default' (determined by the library default; 'pandas' by default)
- **dtype** – [numpy.dtype](#) describing the data.
- **columns** – either number of columns, or a list of columns names.
- **packing** (*str*) – The way the 2D array is packed. Can be either 'flatten' (data is stored row-wise) or 'transposed' (data is stored column-wise).
- **preamble** (*dict*) – If not *None*, defines binary file parameters that supersede the parameters supplied to the function. The defined parameters are 'dtype', 'packing', 'ncols' (number of columns) and 'nrows' (number of rows).
- **skip\_bytes** (*int*) – Number of bytes to skip from the beginning of the file.

**read**(*location\_file*)

Read a file at a given location

**static detect\_file\_format**(*location\_file*)



```
pylablib.core.fileio.loadfile.build_file_format(location_file, file_format='generic', **kwargs)
```

Create file format (*IInputFileFormat* instance) for given parameters and file locations.

If `file_format` is already an instance of *IInputFileFormat*, return unchanged. If `file_format` is generic (e.g., "generic" or "test"), attempt to autodetect it from the file. `**kwargs` are passed to the file format constructor.

```
pylablib.core.fileio.loadfile.load_csv(path=None, out_type='default', dtype='numeric', columns=None,
                                       delimiters=None, empty_entry_substitute=None,
                                       ignore_corrupted_lines=True, skip_lines=0, loc='file',
                                       encoding=None, return_file=False)
```

Load data table from a CSV/table file.

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **out\_type** (*str*) – type of the result: 'array' for numpy array, 'pandas' for pandas DataFrame, or 'default' (determined by the library default; 'pandas' by default)
- **dtype** – dtype of entries; can be either a single type, or a list of types (one per column). Possible dtypes are: 'int', 'float', 'complex', 'numeric' (tries to coerce to minimal possible numeric type, raises error if data can't be converted to *complex*), 'generic' (accept arbitrary types, including lists, dictionaries, escaped strings, etc.), 'raw' (keep raw string).
- **columns** – either a number if columns, or a list of columns names
- **delimiters** (*str*) – regex string which recognizes entries delimiters (by default `r"\s*,\s*|\s+"`, i.e., commas and whitespaces)
- **empty\_entry\_substitute** – substitute for empty table entries. If `None`, all empty table entries are skipped
- **ignore\_corrupted\_lines** (*bool*) – if `True`, skip corrupted (e.g., non-numeric for numeric dtype, or with too few entries) lines; otherwise, raise *ValueError*
- **skip\_lines** (*int*) – number of lines to skip from the beginning of the file
- **loc** (*str*) – location type ("file" means the usual file location; see *location.get\_location()* for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if `True`, return *DataFile* object (contains some metainfo); otherwise, return just the file data

```
pylablib.core.fileio.loadfile.load_csv_desc(path=None, loc='file', encoding=None, return_file=False)
```

Load data from the extended CSV table file.

Analogous to *load\_dict()*, but doesn't allow any additional parameters (which don't matter in this case).

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **loc** (*str*) – location type ("file" means the usual file location; see *location.get\_location()* for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if `True`, return *DataFile* object (contains some metainfo); otherwise, return just the file data

```
pylablib.core.fileio.loadfile.load_bin(path=None, out_type='default', dtype='<f8', columns=None,
                                       packing='flatten', preamble=None, skip_bytes=0, loc='file',
                                       encoding=None, return_file=False)
```

Load data from the binary file.

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **out\_type** (*str*) – type of the result: 'array' for numpy array, 'pandas' for pandas DataFrame, or 'default' (determined by the library default; 'pandas' by default)
- **dtype** – `numpy.dtype` describing the data.
- **columns** – either number of columns, or a list of columns names.
- **packing** (*str*) – The way the 2D array is packed. Can be either 'flatten' (data is stored row-wise) or 'transposed' (data is stored column-wise).
- **preamble** (*dict*) – If not None, defines binary file parameters that supersede the parameters supplied to the function. The defined parameters are 'dtype', 'packing', 'ncols' (number of columns) and 'nrows' (number of rows).
- **skip\_bytes** (*int*) – Number of bytes to skip from the beginning of the file.
- **loc** (*str*) – location type ("file" means the usual file location; see [location.get\\_location\(\)](#) for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if True, return [DataFile](#) object (contains some metainfo); otherwise, return just the file data

```
pylablib.core.fileio.loadfile.load_bin_desc(path=None, loc='file', encoding=None, return_file=False)
```

Load data from the binary file with a description.

Analogous to [load\\_dict\(\)](#), but doesn't allow any additional parameters (which don't matter in this case).

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **loc** (*str*) – location type ("file" means the usual file location; see [location.get\\_location\(\)](#) for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if True, return [DataFile](#) object (contains some metainfo); otherwise, return just the file data

```
pylablib.core.fileio.loadfile.load_dict(path=None, case_normalization=None, inline_dtype='generic',
                                       entry_format='value', inline_out_type='default', skip_lines=0,
                                       allow_duplicate_keys=False, loc='file', encoding=None,
                                       return_file=False)
```

Load data from the dictionary file.

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **case\_normalization** (*str*) – If None, the dictionary paths are case-sensitive; otherwise, defines the way the entries are normalized ('lower' or 'upper').
- **inline\_dtype** (*str*) – dtype for inlined tables.

- **inline\_out\_type** (*str*) – type of the result of the inline table: 'array' for numpy array, 'pandas' for pandas DataFrame, 'raw' for raw [InlineTable](#) data containing tuple (column\_data, column\_names), or 'default' (determined by the library default; 'pandas' by default).
- **entry\_format** (*str*) – Determines the way for dealing with [dict\\_entry.IDictionaryEntry](#) objects (objects transformed into dictionary branches with special recognition rules). Can be 'branch' (don't attempt to recognize those object, leave dictionary as in the file), 'dict\_entry' (recognize and leave as [dict\\_entry.IDictionaryEntry](#) objects) or 'value' (recognize and keep the value).
- **allow\_duplicate\_keys** (*bool*) – if False and the same key is mentioned twice in the file, raise an error
- **skip\_lines** (*int*) – Number of lines to skip from the beginning of the file.
- **loc** (*str*) – location type ("file" means the usual file location; see [location.get\\_location\(\)](#) for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if True, return [DataFile](#) object (contains some meta-info); otherwise, return just the file data

```
pylablib.core.fileio.loadfile.load_generic(path=None, file_format=None, loc='file', encoding=None,
                                           return_file=False, **kwargs)
```

Load data from the file.

#### Parameters

- **path** (*str*) – path to the file of a file-like object
- **file\_format** (*str*) – input file format; if None, attempt to auto-detect file format (same as 'generic'); can also be an [IInputFileFormat](#) instance for specific reading method
- **loc** (*str*) – location type ("file" means the usual file location; see [location.get\\_location\(\)](#) for details)
- **encoding** – if a new file location is opened, this specifies the encoding
- **return\_file** (*bool*) – if True, return [DataFile](#) object (contains some meta-info); otherwise, return just the file data

**\*\*kwargs** are passed to the file formatter used to read the data (see [CSVTableInputFileFormat](#), [DictionaryInputFileFormat](#) and [BinaryTableInputFileFormatter](#) for the possible arguments). The default format names are:

- 'generic': Generic file format. Attempt to autodetect, raise [IOError](#) if unsuccessful;
- 'txt': Generic text file. Attempt to autodetect, raise [IOError](#) if unsuccessful
- 'csv': CSV file, corresponds to [CSVTableInputFileFormat](#);
- 'dict': Dictionary file, corresponds to [DictionaryInputFileFormat](#);
- 'bin': Binary file, corresponds to [BinaryTableInputFileFormatter](#)

## pylablib.core.fileio.loadfile\_utils module

Miscellaneous utilities for reading data files.

`pylablib.core.fileio.loadfile_utils.is_unprintable_character(chn)`

`pylablib.core.fileio.loadfile_utils.detect_binary_file(stream)`

Check if the opened file is binary

`pylablib.core.fileio.loadfile_utils.test_row_type(line)`

Try to determine whether the line is a comment line, a numerical data row, a dictionary row or an unrecognized row.

Doesn't distinguish with a great accuracy; useful only for trying to guess file format.

`pylablib.core.fileio.loadfile_utils.detect_textfile_type(stream)`

Try to autodetect text file type: dictionary or table

`pylablib.core.fileio.loadfile_utils.test_savetime_comment(line)`

Test if the comment resembles a savetime line

`pylablib.core.fileio.loadfile_utils.find_savetime_comment(comments)`

Try to find savetime comment

`pylablib.core.fileio.loadfile_utils.test_columns_line(line, cols_num)`

Test if the line looks like a list of columns for a given columns number

`pylablib.core.fileio.loadfile_utils.find_columns_lines(corrupted, comments, cols_num)`

Try to find a column line (for a given columns number) among the comment and corrupted lines

**class** `pylablib.core.fileio.loadfile_utils.InlineTable(table)`

Bases: `object`

Simple marker class that denotes that the wrapped numpy 2D array should be written inline

`pylablib.core.fileio.loadfile_utils.parse_dict_line(line)`

Parse stripped dictionary file line

`pylablib.core.fileio.loadfile_utils.read_dict_and_comments(f, case_normalization=None,  
 inline_dtype='generic',  
 allow_duplicate_keys=False)`

Load dictionary entries and comments from the file stream.

### Parameters

- **f** – file stream
- **case\_normalization** – case normalization for the returned dictionary; None means that it's case sensitive, "upper" and "lower" determine how they are normalized
- **inline\_dtype** – dtype for inline tables; by default, use the most generic type (can include Python objects such as lists or strings)
- **allow\_duplicate\_keys** – if False and the same key is listed twice, raise an error

Return tuple (data, comment\_lines), where data is a dictionary with parsed entries (tables are still represented as 'raw', i.e., as a tuple of columns list and column names list), and comment\_lines is a list of comment lines

## pylablib.core.fileio.location module

Classes for describing a generic file location.

**class** pylablib.core.fileio.location.**LocationName**(*path=None, ext=None*)

Bases: `object`

File name inside a location.

### Parameters

- **path** – Path inside the location. Gets normalized according to the Dictionary rules (not case-sensitive; '/' and '\' are the delimiters).
- **ext** (*str*) – Name extension (None is default).

**get\_path**(*default\_path="", sep='/'*)

Get the string path.

If the object's *path* is None, use *default\_path* instead. If *sep* is not None, use it to join the path entries; otherwise, return the path in a list form.

**get\_ext**(*default\_ext=""*)

Get the extension.

If the object's *ext* is None, use *default\_ext* instead.

**to\_string**(*default\_path="", default\_ext="", path\_sep='/', ext\_sep='|', add\_empty\_ext=True*)

Convert the path to a string representation.

### Parameters

- **default\_path** (*str*) – Use it as path if the object's *path* is None.
- **default\_ext** (*str*) – Use it as path if the object's *ext* is None.
- **path\_sep** (*str*) – Use it to join the path entries.
- **ext\_sep** (*str*) – Use it to join path and extension.
- **add\_empty\_ext** (*str*) – If False and the extension is empty, don't add *ext\_sep* in the end.

**to\_path**(*default\_path="", default\_ext="", ext\_sep='|', add\_empty\_ext=True*)

Convert the path to a list representation.

Extension is added with *ext\_sep* to the last entry in the path.

### Parameters

- **default\_path** (*str*) – Use it as path if the object's *path* is None.
- **default\_ext** (*str*) – Use it as path if the object's *ext* is None.
- **ext\_sep** (*str*) – Use it to join path and extension.
- **add\_empty\_ext** (*str*) – If False and the extension is empty, don't add *ext\_sep* in the end.

**static from\_string**(*expr, ext\_sep='|'*)

Create a `LocationName` object from a string representation.

*ext\_sep* defines extension separator; the path separators are '/' and '\'. Empty path or extension translate into None.

**static** `from_object(obj)`

Create a `LocationName` object from an object.

`obj` can be a `LocationName` (return unchanged), tuple or list (use as construct arguments), string (treat as a string representation) or `None` (return empty name).

**copy()**

**class** `pylablib.core.fileio.location.LocationFile(loc, name=None)`

Bases: `object`

A file at a location.

Combines information about the location and the name within this location. Can be opened for reading or writing.

**Parameters**

- **loc** – File location.
- **name** – File's name inside the location.

**loc**

File location.

**name**

File's name inside the location.

**opened**

Whether the file is currently opened.

**open**(`mode='read', data_type='text'`)

Open the file.

**Parameters**

- **mode** (`str`) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (`str`) – Either 'text' or 'binary'; if `mode` is an abbreviation, this parameter is ignored (i.e., `open("r", "binary")` still opens file as text).

**close()**

Close the file

**class** `pylablib.core.fileio.location.IDataLocation`

Bases: `object`

Generic location.

**is\_free**(`name=None`)

Check if the name is unoccupied

**generate\_new\_name**(`prefix_name, idx=0`)

Generate a new name inside the location using the given prefix and starting index.

If `idx` is `None`, check just the `prefix_name` first before starting to append indices.

**open**(`name=None, mode='read', data_type='text'`)

Open a location file.

**Parameters**

- **name** – File name inside the location (`None` means 'default' location),

- **mode** (*str*) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (*str*) – Either 'text' or 'binary'; if *mode* is an abbreviation, this parameter is ignored (i.e., `open("r", "binary")` still opens file as text).

**close**(*name*)

Close a location file.

**list\_opened\_files**()

Get a dictionary {*string\_name*: *location\_file*} of all files opened in this location

**class** pylablib.core.fileio.location.**OpenedFileLocation**(*f*, *open\_error=False*, *check\_mode=False*, *check\_data\_type=True*)

Bases: [object](#)

File location which corresponds to an already opened file.

**is\_free**(*name=None*)

**generate\_new\_name**(*prefix\_name*, *idx=0*)

**open**(*name=None*, *mode='read'*, *data\_type='text'*)

**close**(*name*)

**list\_opened\_files**()

**class** pylablib.core.fileio.location.**IFileSystemDataLocation**(*encoding=None*)

Bases: [IDataLocation](#)

A generic filesystem data location.

A single file name describes a single file in the filesystem.

**get\_filesystem\_path**(*name=None*, *path\_type='absolute'*)

Get the filesystem path corresponding to a given name.

*path\_type* can be 'absolute' (return absolute path), 'relative' (return relative path; level depends on the location) or 'name' (only return path inside the location).

**is\_free**(*name=None*)

Check if the name is unoccupied

**open**(*name=None*, *mode='read'*, *data\_type='text'*)

Open a location file.

#### Parameters

- **name** – File name inside the location (None means 'default' location),
- **mode** (*str*) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (*str*) – Either 'text' or 'binary'; if *mode* is an abbreviation, this parameter is ignored (i.e., `open("r", "binary")` still opens file as text).

**close**(*name*)

Close a location file

**list\_opened\_files**()

Get a dictionary {*string\_name*: *location\_file*} of all files opened in this location

**generate\_new\_name**(*prefix\_name*, *idx=0*)

Generate a new name inside the location using the given prefix and starting index.

If *idx* is None, check just the *prefix\_name* first before starting to append indices.

**class** pylablib.core.fileio.location.**SingleFileSystemDataLocation**(*file\_path*, *encoding=None*)

Bases: *IFileSystemDataLocation*

A location describing a single file.

Any use of a non-default name raises *ValueError*.

#### Parameters

**file\_path** (*str*) – The path to the file.

**get\_filesystem\_path**(*name=None*, *path\_type='absolute'*)

Get the filesystem path corresponding to a given name.

*path\_type* can be 'absolute' (return absolute path), 'relative' (return relative path; level depends on the location) or 'name' (only return path inside the location).

**close**(*name*)

Close a location file

**generate\_new\_name**(*prefix\_name*, *idx=0*)

Generate a new name inside the location using the given prefix and starting index.

If *idx* is None, check just the *prefix\_name* first before starting to append indices.

**is\_free**(*name=None*)

Check if the name is unoccupied

**list\_opened\_files**()

Get a dictionary {*string\_name*: *location\_file*} of all files opened in this location

**open**(*name=None*, *mode='read'*, *data\_type='text'*)

Open a location file.

#### Parameters

- **name** – File name inside the location (None means 'default' location),
- **mode** (*str*) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (*str*) – Either 'text' or 'binary'; if *mode* is an abbreviation, this parameter is ignored (i.e., open("r", "binary") still opens file as text).

**class** pylablib.core.fileio.location.**PrefixedFileSystemDataLocation**(*file\_path*,  
*prefix\_template='{0}\_{1}'*,  
*encoding=None*)

Bases: *IFileSystemDataLocation*

A location describing a set of prefixed files.

#### Parameters

- **file\_path** (*str*) – A master path. Its name is used as a prefix, and its extension is used as a default.
- **prefix\_template** (*str*) – A *str.format()* string for generating prefixed files. Has two arguments: the first is the master name, the second is the *sub\_location*.



Multi-level paths translate into nested folders (the top level folder is combined from the *file\_path* prefix and the first path entry).

**get\_filesystem\_path**(*name=None, path\_type='absolute'*)

Get the filesystem path corresponding to a given name.

*path\_type* can be 'absolute' (return absolute path), 'relative' (return relative path; level depends on the location) or 'name' (only return path inside the location).

**close**(*name*)

Close a location file

**generate\_new\_name**(*prefix\_name, idx=0*)

Generate a new name inside the location using the given prefix and starting index.

If *idx* is None, check just the *prefix\_name* first before starting to append indices.

**is\_free**(*name=None*)

Check if the name is unoccupied

**list\_opened\_files**()

Get a dictionary {*string\_name*: *location\_file*} of all files opened in this location

**open**(*name=None, mode='read', data\_type='text'*)

Open a location file.

#### Parameters

- **name** – File name inside the location (None means 'default' location),
- **mode** (*str*) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (*str*) – Either 'text' or 'binary'; if *mode* is an abbreviation, this parameter is ignored (i.e., open("r", "binary") still opens file as text).

```
class pylablib.core.fileio.location.FolderFileSystemDataLocation(folder_path,
                                                                default_name='content',
                                                                default_ext='',
                                                                encoding=None)
```

Bases: [IFileSystemDataLocation](#)

A location describing a single folder.

#### Parameters

- **folder\_path** (*str*) – A path to the folder. Can also have one or two '|' symbols in the end (e.g., 'folder|file|dat'), which separate default name and extension (overrides *default\_name* and *default\_ext* parameters)
- **default\_name** (*str*) – The default file name.
- **default\_ext** (*str*) – The default file extension.

Multi-level paths translate into nested subfolders.

**get\_filesystem\_path**(*name=None, path\_type='absolute'*)

Get the filesystem path corresponding to a given name.

*path\_type* can be 'absolute' (return absolute path), 'relative' (return relative path; level depends on the location) or 'name' (only return path inside the location).

**close**(*name*)

Close a location file

**generate\_new\_name**(*prefix\_name*, *idx=0*)

Generate a new name inside the location using the given prefix and starting index.

If *idx* is *None*, check just the *prefix\_name* first before starting to append indices.

**is\_free**(*name=None*)

Check if the name is unoccupied

**list\_opened\_files**()

Get a dictionary {*string\_name*: *location\_file*} of all files opened in this location

**open**(*name=None*, *mode='read'*, *data\_type='text'*)

Open a location file.

#### Parameters

- **name** – File name inside the location (*None* means 'default' location),
- **mode** (*str*) – Opening mode. Can be 'read', 'write' or 'append', as well as standard abbreviation (e.g., "r" or "wb").
- **data\_type** (*str*) – Either 'text' or 'binary'; if *mode* is an abbreviation, this parameter is ignored (i.e., `open("r", "binary")` still opens file as text).

`pylablib.core.fileio.location.get_location(path, loc, *args, **kwargs)`

Build a location.

If *path* or *loc* are instances of *IDataLocation*, return them unchanged. If *loc* is a string, it describes location kind:

- 'single\_file': *SingleFileSystemDataLocation* with the given *path*.
- 'file' or 'prefixed\_file': *PrefixedFileSystemDataLocation* with the given *path* as a master path.
- 'folder': *FolderFileSystemDataLocation* with the given folder *path*.

Any additional arguments are relayed to the constructors.

## pylablib.core.fileio.parse\_csv module

Utilities for parsing CSV files.

**class** `pylablib.core.fileio.parse_csv.ChunksAccumulator`(*dtype='numeric'*,  
*ignore\_corrupted\_lines=True*,  
*trim\_rows=False*)

Bases: *object*

Class for accumulating data chunks into a single array.

#### Parameters

- **dtype** – dtype of entries; can be either a single type, or a list of types (one per column). Possible dtypes are: 'int', 'float', 'complex', 'numeric' (tries to coerce to minimal possible numeric type, raises error if data can't be converted to complex), 'generic' (accept arbitrary types, including lists, dictionaries, escaped strings, etc.), 'raw' (keep raw string).

- **ignore\_corrupted\_lines** – if True, skip corrupted (e.g., non-numeric for numeric dtype, or with too few entries) lines; otherwise, raise [ValueError](#).
- **trim\_rows** – if True and the row length is larger than expected, drop extra entries; otherwise, treat the row as corrupted

**corrupted\_number()**

**convert\_columns**(*raw\_columns*)

Convert raw columns into appropriate data structure (numpy array for numeric dtypes, list for generic and raw).

**add\_columns**(*columns*)

Append columns (lists or numpy arrays) to the existing data.

**add\_chunk**(*chunk*)

Add a chunk (2D list) to the pre-existing data.

```
pylablib.core.fileio.parse_csv.read_columns(f, dtype, delimiters='\s*,\s*|\s+',
                                             empty_entry_substitute=None,
                                             ignore_corrupted_lines=True, trim_rows=False,
                                             stop_comment=None)
```

Load columns from the file stream *f*.

#### Parameters

- **dtype** – dtype of entries; can be either a single type, or a list of types (one per column). Possible dtypes are: 'int', 'float', 'complex', 'numeric' (tries to coerce to minimal possible numeric type, raises error if data can't be converted to complex), 'generic' (accept arbitrary types, including lists, dictionaries, escaped strings, etc.), 'raw' (keep raw string).
- **delimiters** (*str*) – Regex string which recognizes delimiters (by default `r"\s*,\s*|\s+"`, i.e., commas and whitespaces).
- **empty\_entry\_substitute** – Substitute for empty table entries. If None, all empty table entries are skipped.
- **ignore\_corrupted\_lines** – If True, skip corrupted (e.g., non-numeric for numeric dtype, or with too few entries) lines; otherwise, raise [ValueError](#).
- **trim\_rows** – if True and the row length is larger than expected, drop extra entries; otherwise, treat the row as corrupted
- **stop\_comment** (*str*) – Regex string for the stopping comment. If not None. the function will stop if comment satisfying *stop\_comment* regex is encountered.

#### Returns

(*columns*, *comments*, *corrupted\_lines*).

*columns* is a list of columns with data.

*comments* is a list of comment strings.

*corrupted\_lines* is a dict {'size':list, 'type':list} of corrupted lines (already split into entries), based on the corruption type ('size' means too small size, 'type' means it couldn't be converted using provided dtype).

#### Return type

[tuple](#)

```
pylablib.core.fileio.parse_csv.columns_to_table(data, columns=None, dtype='numeric',
                                                out_type='columns')
```

Convert *data* (columns list) into a table.

#### Parameters

- **columns** – either number if columns, or a list of columns names.
- **out\_type** (*str*) – type of the result: 'array' for numpy array, 'pandas' for pandas DataFrame, 'columns' for tuple (data, columns)

```
pylablib.core.fileio.parse_csv.read_table(f, dtype='numeric', columns=None, out_type='columns',
                                          delimiters=\\s*,\\s*|\\s+', empty_entry_substitute=None,
                                          ignore_corrupted_lines=True, trim_rows=False,
                                          stop_comment=None)
```

Load table from the file stream *f*.

Arguments are the same as in *read\_columns()* and *columns\_to\_table()*.

#### Returns

(table, comments, corrupted\_lines).

*table* is a table of the format *out\_type*.

*corrupted\_lines* is a dict {'size':list, 'type':list} of corrupted lines (already split into entries), based on the corruption type ('size' means too small size, 'type' means it couldn't be converted using provided dtype).

*comments* is a list of comment strings.

#### Return type

tuple

## pylablib.core.fileio.savefile module

Utilities for writing data files.

```
class pylablib.core.fileio.savefile.IOutputFileFormat(format_name)
```

Bases: *object*

Generic class for an output file format.

#### Parameters

**format\_name** (*str*) – The name of the format (to be defined in subclasses).

```
write_file(location_file, to_save)
```

```
write_data(location_file, data)
```

```
write(location_file, data)
```

```
class pylablib.core.fileio.savefile.ITextOutputFileFormat(format_name, save_props=True,
                                                           save_comments=True, save_time=True,
                                                           new_time=True)
```

Bases: *IOutputFileFormat*

Generic class for a text output file format.

#### Parameters

- **format\_name** (*str*) – The name of the format (to be defined in subclasses).

- **save\_props** (*bool*) – If True and saving *datafile.DataFile* object, save its props metainfo.
- **save\_comments** (*bool*) – If True and saving *datafile.DataFile* object, save its comments metainfo.
- **save\_time** (*bool*) – If True, append the file creation time in the end.
- **new\_time** (*bool*) – If saving *datafile.DataFile* object, determines if the time should be updated to the current time.

**make\_comment\_line**(*comment*)

**make\_prop\_line**(*name*, *value*)

**make\_savetime\_line**(*time*)

**static write\_line**(*stream*, *line*)

**write\_comments**(*stream*, *comments*)

**write\_props**(*stream*, *props*)

**write\_savetime**(*stream*, *time*)

**write\_file**(*location\_file*, *to\_save*)

**write**(*location\_file*, *data*)

**write\_data**(*location\_file*, *data*)

```
class pylablib.core.fileio.savefile.CSVTableOutputFileFormat(delimiters='\t', value_formats=None,
                                                             use_rep_classes=False,
                                                             save_columns=True,
                                                             save_props=True,
                                                             save_comments=True,
                                                             save_time=True)
```

Bases: *ITextOutputFileFormat*

Class for CSV output file format.

#### Parameters

- **delimiters** (*str*) – Used to separate entries in a row.
- **value\_formats** (*str*) – If not None, defines value formats to be passed to *utils.string.to\_string()* function.
- **use\_rep\_classes** (*bool*) – If True, use representation classes for Dictionary entries (e.g., numpy arrays will be represented as "array([1, 2, 3])" instead of just "[1, 2, 3]"); This improves storage fidelity, but makes result harder to parse (e.g., by external string parsers).
- **save\_columns** (*bool*) – If True, save column names as a comment line in the beginning of the file.
- **save\_props** (*bool*) – If True and saving *datafile.DataFile* object, save its props metainfo.
- **save\_comments** (*bool*) – If True and saving *datafile.DataFile* object, save its comments metainfo.
- **save\_time** (*bool*) – If True, append the file creation time in the end.

**get\_table\_line**(*line*)

**get\_columns\_line**(*columns*)

**write\_data**(*location\_file*, *data*)

Write data to a CSV file.

#### Parameters

- **location\_file** – Location of the destination.
- **data** – Data to be saved. Can be a pandas DataFrame or an arbitrary 2D array (numpy array, 2D list, etc.); if the data is not DataFrame or numpy 2D array, it gets converted into a DataFrame using the standard constructor (i.e., 2D list is interpreted as a list of rows)

**make\_comment\_line**(*comment*)

**make\_prop\_line**(*name*, *value*)

**make\_savetime\_line**(*time*)

**write**(*location\_file*, *data*)

**write\_comments**(*stream*, *comments*)

**write\_file**(*location\_file*, *to\_save*)

**static write\_line**(*stream*, *line*)

**write\_props**(*stream*, *props*)

**write\_savetime**(*stream*, *time*)

```
class pylablib.core.fileio.savefile.DictionaryOutputFileFormat(param_formats=None,  
                                                                use_rep_classes=False,  
                                                                table_format='inline',  
                                                                inline_delimiters='\t',  
                                                                inline_formats=None,  
                                                                save_props=True,  
                                                                save_comments=True,  
                                                                save_time=True)
```

Bases: [\*ITextOutputFileFormat\*](#)

Class for Dictionary output file format.

#### Parameters

- **param\_formats** (*str*) – If not None, defines value formats to be passed to [\*utils.string.to\\_string\(\)\*](#) function when writing Dictionary entries.
- **use\_rep\_classes** (*bool*) – If True, use representation classes for Dictionary entries (e.g., numpy arrays will be represented as "array([1, 2, 3])" instead of just "[1, 2, 3]"); This improves storage fidelity, but makes result harder to parse (e.g., by external string parsers).
- **table\_format** (*str*) – Default format for table (numpy arrays or pandas DataFrames) entries. Can be 'inline' (table is written inside the file), 'csv' (external CSV file) or 'bin' (external binary file).
- **inline\_delimiters** (*str*) – Used to separate entries in a row for inline tables.

- **inline\_formats** (*str*) – If not None, defines value formats to be passed to *utils.string.to\_string()* function when writing inline tables.
- **save\_props** (*bool*) – If True and saving *datafile.DataFile* object, save its props metainfo.
- **save\_comments** (*bool*) – If True and saving *datafile.DataFile* object, save its comments metainfo.
- **save\_time** (*bool*) – If True, append the file creation time in the end.

**get\_dictionary\_line**(*path, value*)

**write\_data**(*location\_file, data*)

Write data to a Dictionary file.

#### Parameters

- **location\_file** – Location of the destination.
- **data** – Data to be saved. Should be object of class *Dictionary*.

**make\_comment\_line**(*comment*)

**make\_prop\_line**(*name, value*)

**make\_savetime\_line**(*time*)

**write**(*location\_file, data*)

**write\_comments**(*stream, comments*)

**write\_file**(*location\_file, to\_save*)

**static write\_line**(*stream, line*)

**write\_props**(*stream, props*)

**write\_savetime**(*stream, time*)

**class** *pylablib.core.fileio.savefile.IBinaryOutputFileFormat*(*format\_name*)

Bases: *IOutputFileFormat*

**get\_preamble**(*location\_file, data*)

**write**(*location\_file, data*)

**write\_data**(*location\_file, data*)

**write\_file**(*location\_file, to\_save*)

**class** *pylablib.core.fileio.savefile.TableBinaryOutputFileFormat*(*dtype=None, transposed=False*)

Bases: *IBinaryOutputFileFormat*

Class for binary output file format.

#### Parameters

- **dtype** – a string with numpy dtype (e.g., "<f8") used to save the data. By default, use little-endian ("<") variant kind of the supplied data array dtype
- **transposed** (*bool*) – If False, write the data row-wise; otherwise, write it column-wise.

**get\_dtype**(*table*)

**get\_preamble**(*location\_file*, *data*)

Generate a preamble (dictionary describing the file format).

The parameters are 'dtype', 'packing' ('transposed' or 'flatten', depending on the *transposed* attribute), 'ncol' (number of columns) and 'nrows' (number of rows).

**write\_data**(*location\_file*, *data*)

Write data to a binary file.

#### Parameters

- **location\_file** – Location of the destination.
- **data** – Data to be saved. Can be a pandas DataFrame or an arbitrary 2D array (numpy array, 2D list, etc.) Converted to numpy array before saving.

**write\_file**(*location\_file*, *to\_save*)

**write**(*location\_file*, *data*)

`pylablib.core.fileio.savefile.get_output_format(data, output_format, **kwargs)`

`pylablib.core.fileio.savefile.save_csv(data, path, delimiters='\t', value_formats=None, use_rep_classes=False, save_columns=True, save_props=True, save_comments=True, save_time=True, loc='file', encoding=None)`

Save data to a CSV file.

#### Parameters

- **data** – Data to be saved (2D numpy array, pandas DataFrame, or a [datafile.DataFile](#) object containing this data).
- **path** (*str*) – Path to the file or a file-like object.
- **delimiters** (*str*) – Used to separate entries in a row.
- **value\_formats** (*str*) – If not None, defines value formats to be passed to [utils.string.to\\_string\(\)](#) function.
- **use\_rep\_classes** (*bool*) – If True, use representation classes for Dictionary entries (e.g., numpy arrays will be represented as "array([1, 2, 3])" instead of just "[1, 2, 3]"); This improves storage fidelity, but makes result harder to parse (e.g., by external string parsers).
- **save\_columns** (*bool*) – If True, save column names as a comment line in the beginning of the file.
- **save\_props** (*bool*) – If True and saving [datafile.DataFile](#) object, save its props metainfo.
- **save\_comments** (*bool*) – If True and saving [datafile.DataFile](#) object, save its comments metainfo.
- **save\_time** (*bool*) – If True, append the file creation time in the end.
- **loc** (*str*) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.



`pylablib.core.fileio.savefile.save_csv_desc(data, path, loc='file', encoding=None)`

Save data table to a dictionary file with an inlined table.

Compared to `save_csv()`, supports more pandas features (index, column multi-index), but can only be directly read by pylablib.

#### Parameters

- **data** – Data to be saved (2D numpy array, pandas DataFrame, or a `datafile.DataFile` object containing this data).
- **path** (`str`) – Path to the file or a file-like object.
- **loc** (`str`) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.

`pylablib.core.fileio.savefile.save_bin(data, path, dtype=None, transposed=False, loc='file', encoding=None)`

Save data to a binary file.

#### Parameters

- **data** – Data to be saved (2D numpy array, pandas DataFrame, or a `datafile.DataFile` object containing this data).
- **path** (`str`) – Path to the file or a file-like object.
- **dtype** – `numpy.dtype` describing the data. By default, use little-endian ("`<`") variant kind of the supplied data array dtype.
- **transposed** (`bool`) – If `False`, write the data row-wise; otherwise, write it column-wise.
- **loc** (`str`) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.

`pylablib.core.fileio.savefile.save_bin_desc(data, path, loc='file', encoding=None)`

Save data to a binary file with an additional description file, which contains all of the data related to loading (shape, dtype, columns, etc.)

#### Parameters

- **data** – Data to be saved (2D numpy array, pandas DataFrame, or a `datafile.DataFile` object containing this data).
- **path** (`str`) – Path to the file or a file-like object.
- **loc** (`str`) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.

`pylablib.core.fileio.savefile.save_dict(data, path, param_formats=None, use_rep_classes=False, table_format='inline', inline_delimiters='\t', inline_formats=None, save_props=True, save_comments=True, save_time=True, loc='file', encoding=None)`

Save dictionary to a text file.

#### Parameters

- **data** – Data to be saved.
- **path** (`str`) – Path to the file or a file-like object.

- **param\_formats** (*str*) – If not None, defines value formats to be passed to [utils.string.to\\_string\(\)](#) function when writing Dictionary entries.
- **use\_rep\_classes** (*bool*) – If True, use representation classes for Dictionary entries (e.g., numpy arrays will be represented as "array([1, 2, 3])" instead of just "[1, 2, 3]"); This improves storage fidelity, but makes result harder to parse (e.g., by external string parsers).
- **table\_format** (*str*) – Default format for table (numpy arrays or pandas DataFrames) entries. Can be 'inline' (table is written inside the file), 'csv' (external CSV file) or 'bin' (external binary file).
- **inline\_delimiters** (*str*) – Used to separate entries in a row for inline tables.
- **inline\_formats** (*str*) – If not None, defines value formats to be passed to [utils.string.to\\_string\(\)](#) function when writing inline tables.
- **save\_props** (*bool*) – If True and saving [datafile.DataFile](#) object, save its props metainfo.
- **save\_comments** (*bool*) – If True and saving [datafile.DataFile](#) object, save its comments metainfo.
- **save\_time** (*bool*) – If True, append the file creation time in the end.
- **loc** (*str*) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.

```
pylablib.core.fileio.savefile.save_generic(data, path, output_format=None, loc='file', encoding=None,
                                           **kwargs)
```

Save data to a file.

#### Parameters

- **data** – Data to be saved.
- **path** (*str*) – Path to the file or a file-like object.
- **output\_format** (*str*) – Output file format. Can be either None (defaults to 'csv' for table data and 'dict' for Dictionary data), a string with one of the default format names, or an already prepared [IOOutputFileFormat](#) object.
- **loc** (*str*) – Location type.
- **encoding** – if a new file location is opened, this specifies the encoding.

*\*\*kwargs* are passed to the file formatter constructor (see [CSVTableOutputFileFormat](#), [DictionaryOutputFileFormat](#) and [TableBinaryOutputFileFormat](#) for the possible arguments). The default format names are:

- 'csv': CSV file, corresponds to [CSVTableOutputFileFormat](#) and [save\\_csv\(\)](#);
- 'csv\_desc': CSV file with an additional dictionary containing format description, corresponds to [DictionaryOutputFileFormat](#) and [save\\_csv\\_desc\(\)](#);
- 'bin': Binary file, corresponds to [TableBinaryOutputFileFormat](#) and [save\\_bin\(\)](#);
- 'bin\_desc': Binary file with an additional dictionary containing format description, corresponds to [DictionaryOutputFileFormat](#) and [save\\_bin\\_desc\(\)](#);
- 'dict': Dictionary file, corresponds to [DictionaryOutputFileFormat](#) and [save\\_dict\(\)](#)

## pylablib.core.fileio.table\_stream module

```
class pylablib.core.fileio.table_stream.TableStreamFile(path, columns=None, delimiter='\t',
                                                         fmt=None, add_timestamp=False,
                                                         header_prepend='# ')
```

Bases: `object`

Expanding table file.

Can define column names and formats for different columns, and repeatedly write data into the same file. Useful for, e.g., continuous log files.

### Parameters

- **path** (*str*) – Path to the destination file.
- **columns** (*list*) – If not `None`, it's a list of column names to be added as a header on creation.
- **delimiter** (*str*) – Values delimiter.
- **fmt** (*str*) – If not `None`, it's a list of format strings for the line entries (e.g., `". 3f"`); instead of format string one can also be `None`, which means using the standard `to_string()` conversion function
- **add\_timestamp** (*bool*) – If `True`, add the UNIX timestamp in the beginning of each line (columns and format are expanded accordingly)
- **header\_prepend** – the string to prepend to the header line; by default, a comment symbol, which is best compatibly with `loadfile.load_csv()` function

### **write\_text\_lines**(*lines*)

Write several text lines into the file.

Create the file if it doesn't exist (in which case the header is automatically added).

#### Parameters

**lines** (*[str]*) – List of lines to write.

### **write\_row**(*row*)

Write a single data row into the file.

Create the file if it doesn't exist (in which case the header is automatically added).

#### Parameters

**data** (*list* or *numpy.ndarray*) – Data row to be added.

### **write\_multiple\_rows**(*rows*)

Write a multiple data lines into the file.

Create the file if it doesn't exist (in which case the header is automatically added).

#### Parameters

**rows** (*[list* or *numpy.ndarray]*) – Data rows to be added.

## Module contents

### pylablib.core.gui package

#### Subpackages

### pylablib.core.gui.widgets package

#### Submodules

### pylablib.core.gui.widgets.button module

**class** pylablib.core.gui.widgets.button.**ToggleButton**(*parent=None*)

Bases: `object`

Expanded toggle button.

Maintains internally stored consistent value (which can be, e.g., accessed from different threads). Allows setting different captions of pressed/unpressed, and uses those to represent values.

**set\_value\_labels**(*labels*)

Set a list of values corresponding to combo box indices.

Can be either a list of values, whose length must be equal to the number of options, or `None` (don't change the button label on toggle).

**value\_changed** = `<Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>`

Signal emitted when value is changed

**get\_value**()

Get current value

**set\_value**(*value*, *notify\_value\_change=True*)

Set current value.

If `notify_value_change==True`, emit the `value_changed` signal; otherwise, change value silently.

**repr\_value**(*value*)

Return representation of *value* as a caption text

### pylablib.core.gui.widgets.button\_selector module

**class** pylablib.core.gui.widgets.button\_selector.**ButtonSelector**(*parent*)

Bases: `object`

Button selector widget.

Similar to combo-box, but displays all options in a single row of buttons.

**set\_out\_of\_range**(*action='error'*)

Set behavior when out-of-range value is applied.

Can be "error" (raise error), "reset" (reset to no-value position), "reset\_start" (reset to the first position) or "ignore" (keep current value).

**set\_direct\_index\_action**(*action='error'*)

Set behavior when index values are specified, but direct indexing is used.

Can be "ignore" (do not allow direct indexing and treat any value as index value), "value\_default" (allow direct indexing, but prioritize index values with the same value), or "index\_default" (allow direct indexing and prioritize it if index value with the same value exists).

**index\_to\_value**(*idx*)

Turn numerical index into value

**value\_to\_index**(*value*)

Turn value into a numerical index

**keep = keep**

**none = none**

**iterbuttons**()

Iterate over all selecting buttons

**set\_buttons\_width**(*width*)

Set the fixed width of all the buttons

**set\_index\_values**(*index\_values, value=keep, index=None, unselected\_value=keep*)

Set a list of values corresponding to combo box indices.

Can be either a list of values, whose length must be equal to the number of options, or `None` (simply use indices). Note: if the number of combo box options changed (e.g., using `addItem` or `insertItem` methods), the index values need to be manually updated; otherwise, the errors might arise if the index is larger than the number of values. If *value* is specified, set as the new values. If *index* is specified, use it as the index of a new value; if both *value* and *index* are specified, the *value* takes priority. If *unselected\_value* is supplied, it specifies which value corresponds to no combo box value being selected (by default, keep the current value).

**get\_index\_values**()

Return the list of values corresponding to combo box indices

**get\_options**()

Return the list of labels corresponding to combo box indices

**get\_options\_dict**()

Return the dictionary {*value*: *label*} of the option labels

**set\_options**(*options, index\_values=None, value=keep, index=None, unselected\_value=keep*)

Set new set of options.

If *index\_values* is not `None`, set these as the new index values; otherwise, index values are reset. If *options* is a dictionary, interpret it as a mapping {*option*: *index\_value*}. If *value* is specified, set as the new values. If *index* is specified, use it as the index of a new value; if both *value* and *index* are specified, the *value* takes priority. If *unselected\_value* is supplied, it specifies which value corresponds to no combo box value being selected (by default, keep the current value).

**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value**()

Get current numerical value

**set\_value**(*value*, *notify\_value\_change=True*)

Set current value.

If *notify\_value\_change==True*, emit the *value\_changed* signal; otherwise, change value silently.

**repr\_value**(*value*)

Return representation of *value* as a combo box text

## pylablib.core.gui.widgets.combo\_box module

**class** pylablib.core.gui.widgets.combo\_box.**ComboBox**(*parent*)

Bases: `object`

Expanded combo box.

Maintains internally stored consistent value (which can be, e.g., accessed from different threads). Allows setting values which are reported via *value\_changed* signal instead of simple indices.

**wheelEvent**(*event*)

**set\_out\_of\_range**(*action='error'*)

Set behavior when out-of-range value is applied.

Can be "error" (raise error), "reset" (reset to no-value position), "reset\_start" (reset to the first position) or "ignore" (keep current value).

**set\_direct\_index\_action**(*action='error'*)

Set behavior when index values are specified, but direct indexing is used.

Can be "ignore" (do not allow direct indexing and treat any value as index value), "value\_default" (allow direct indexing, but prioritize index values with the same value), or "index\_default" (allow direct indexing and prioritize it if index value with the same value exists).

**index\_to\_value**(*idx*)

Turn numerical index into value

**value\_to\_index**(*value*)

Turn value into a numerical index

**keep = keep**

**none = none**

**set\_index\_values**(*index\_values*, *value=None*, *index=None*, *unselected\_value=keep*)

Set a list of values corresponding to combo box indices.

Can be either a list of values, whose length must be equal to the number of options, or `None` (simply use indices). Note: if the number of combo box options changed (e.g., using `addItem` or `insertItem` methods), the index values need to be manually updated; otherwise, the errors might arise if the index is larger than the number of values. If *value* is specified, set as the new values. If *index* is specified, use it as the index of a new value; if both *value* and *index* are specified, the *value* takes priority. If *unselected\_value* is supplied, it specifies which value corresponds to no combo box value being selected (by default, keep the current value).

**get\_index\_values**()

Return the list of values corresponding to combo box indices

**get\_options()**

Return the list of labels corresponding to combo box indices

**get\_options\_dict()**

Return the dictionary {*value*: *label*} of the option labels

**set\_options**(*options*, *index\_values=None*, *value=None*, *index=None*, *unselected\_value=keep*)

Set new set of options.

If *index\_values* is not *None*, set these as the new index values; otherwise, index values are reset. If *options* is a dictionary, interpret it as a mapping {*option*: *index\_value*}. If *value* is specified, set as the new values. If *index* is specified, use it as the index of a new value; if both *value* and *index* are specified, the *value* takes priority. If *unselected\_value* is supplied, it specifies which value corresponds to no combo box value being selected (by default, keep the current value).

**insert\_option**(*option*, *index\_value=None*, *index=None*)

Insert or append a new option to the list

Insertion (i.e., *index* is not *None*) only works for index-valued combo boxes.

**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value()**

Get current numerical value

**set\_value**(*value*, *notify\_value\_change=True*)

Set current value.

If *notify\_value\_change==True*, emit the *value\_changed* signal; otherwise, change value silently.

**repr\_value**(*value*)

Return representation of *value* as a combo box text

**pylablib.core.gui.widgets.container module****class** pylablib.core.gui.widgets.container.**TTimer**(*name*, *period*, *timer*)

Bases: `tuple`

**name**

**period**

**timer**

**class** pylablib.core.gui.widgets.container.**TTimerEvent**(*start*, *loop*, *stop*, *timer*)

Bases: `tuple`

**loop**

**start**

**stop**

**timer**

**class** pylablib.core.gui.widgets.container.**TChild**(*name*, *widget*, *gui\_values\_path*)

Bases: `tuple`

**gui\_values\_path**

**name**

**widget**

**class** pylablib.core.gui.widgets.container.IQContainer(\*args, name=None, \*\*kwargs)

Bases: [object](#)

Basic controller object which combines and controls several other widget.

Can either corresponds to a widget (e.g., a frame or a group box), or simply be an organizing entity.

#### Parameters

**name** – entity name (used by default when adding this object to a values table)

Abstract mix-in class, which needs to be added to a class inheriting from `QObject`. Alternatively, one can directly use [QContainer](#), which already inherits from `QObject`.

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**contained\_value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**setup\_name**(name)

Set the object's name

**setup**(name=None)

Setup the container by initializing its GUI values and setting the `ctl` attribute

**add\_timer**(name, period, autostart=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If `autostart==True` and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**start\_timer**(name)

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop\_timer**(name)

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**is\_timer\_running**(name)

Check if the timer with the given name is running

**add\_timer\_event**(name, loop=None, start=None, stop=None, period=None, timer=None, autostart=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If `autostart==True` and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_child\_values**(name, widget, path, add\_change\_event=True)

Add child's values to the container's table.

If *widget* is a container and *path*=="" or ends in "/"\* (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the



given path. if `add_change_event==True`, changing of the widget's value emits the container's `contained_value_changed` event

**add\_child**(*name*, *widget*, *gui\_values\_path=True*, *add\_change\_event=True*)

Add a contained child widget.

If *gui\_values\_path* is `False` or `None`, do not add it to the GUI values table; if it is `True`, add it under the same root (*path*==`""`) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored. if `add_change_event==True`, changing of the widget's value emits the container's `contained_value_changed` event

**get\_child**(*name*)

Get the child widget with the given name

**remove\_child**(*name*, *clear=True*)

Remove child from the container and (if *clear==True*) clear it

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**start**()

Start the container.

Starts all the internal timers, and calls `start` method for all the contained widgets.

**stop**()

Stop the container.

Stops all the internal timers, and calls `stop` method for all the contained widgets.

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**clear**()

Clear the container.

Stop all timers and widgets, and call `clear` methods of all contained widgets, remove all widgets from the values table, remove all widgets from the table.

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_all\_values**()

Get values of all widget in the container

**set\_value**(*name, value*)

Set value of a widget with the given name (None means all values)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is None, emit for all values in the table.

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (None means all indicators)

**get\_all\_indicators**()

Get indicator values of all widget in the container

**set\_indicator**(*name, value, ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_all\_indicators**(*value, ignore\_missing=True*)

**update\_indicators**()

Update all indicators to represent current values

**class** pylablib.core.gui.widgets.container.QContainer(\*args, name=None, \*\*kwargs)

Bases: [IQContainer](#), [object](#)

Basic controller object which combines and controls several other widget.

Can either corresponds to a widget (e.g., a frame or a group box), or simply be an organizing entity.

#### Parameters

**name** – entity name (used by default when adding this object to a values table)

Simply a combination of [IQContainer](#) and [QObject](#).

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(*name, widget, gui\_values\_path=True, add\_change\_event=True*)

Add a contained child widget.

If *gui\_values\_path* is False or None, do not add it to the GUI values table; if it is True, add it under the same root (*path=""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored. if *add\_change\_event==True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_child\_values**(*name*, *widget*, *path*, *add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path*=="" or ends in "/"\* (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event*==True, changing of the widget's value emits the container's `contained_value_changed` event

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator*==True, add default (stored value) indicator handler as well.

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling `start()` method), start the timer as well.

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued*==True, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator*==True, add default indicator handler as well.

**clear()**

Clear the container.

Stop all timers and widgets, and call `clear` methods of all contained widgets, remove all widgets from the values table, remove all widgets from the table.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators()**

Get indicator values of all widget in the container

**get\_all\_values()**

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (None means all indicators)

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**remove\_child**(*name, clear=True*)

Remove child from the container and (if *clear==True*) clear it

**set\_all\_indicators**(*value, ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**set\_indicator**(*name, value, ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_value**(*name, value*)

Set value of a widget with the given name (None means all values)

**setup**(*name=None*)

Setup the container by initializing its GUI values and setting the *ctl* attribute

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls *start* method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on *start()* method)

**stop**()

Stop the container.

Stops all the internal timers, and calls *stop* method for all the contained widgets.

**stop\_timer**(*name*)

Stop the timer with the given name (also called automatically on *stop()* method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

**class pylablib.core.gui.widgets.container.IQWidgetContainer(\*args, \*\*kwargs)**

Bases: *IQLayoutManagedWidget*, *IQContainer*

Generic widget container.

Combines *IQContainer* management of GUI values and timers with *IQLayoutManagedWidget* management of the contained widget's layout.

Typically, adding widget adds them both to the container values and to the layout; however, this can be skipped by either using *QLayoutManagedWidget.add\_to\_layout()* (only add to the layout), or specifying *location="skip"* in *add\_child()* (only add to the container).

Abstract mix-in class, which needs to be added to a class inheriting from *QWidget*. Alternatively, one can directly use *QWidgetContainer*, which already inherits from *QWidget*.

**setup(layout='vbox', no\_margins=False, name=None)**

Setup the layout.

**Parameters**

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**add\_child(name, widget, location=None, gui\_values\_path=True)**

Add a contained child widget.

*name* specifies the child storage name; if *name==False*, only add the widget to the layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location=="skip"*, skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when *clear* or *remove\_child* methods are called; otherwise, simply its *clear* method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path=""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**remove\_child(name, clear=True)**

Remove widget from the container and the layout and (if *clear==True*) clear it, and remove it

**add\_frame(name, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)**

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins==True*, the frame will have no inner layout margins. The other parameters are the same as in *add\_child()* method.

**add\_group\_box**(*name*, *caption*, *layout*='vbox', *location*=None, *gui\_values\_path*=True, *no\_margins*=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==True, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**clear()**

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child\_values**(*name*, *widget*, *path*, *add\_change\_event*=True)

Add child's values to the container's table.

If *widget* is a container and *path*=="" or ends in "/" (e.g., "subpath/"), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. If *add\_change\_event*==True, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_decoration\_label**(*text*, *location*='next', *tag*=None)

Add a decoration text label with the given text

**add\_padding**(*kind*='auto', *location*='next', *stretch*=0, *tag*=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name*, *getter*=None, *setter*=None, *add\_indicator*=True)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator*==True, add default (stored value) indicator handler as well.

**add\_spacer**(*height*=0, *width*=0, *stretch\_height*=False, *stretch\_width*=False, *stretch*=0, *location*='next', *tag*=None)

Add a spacer with the given width and height to the given location.

If *stretch\_height*==True or *stretch\_width*==True, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*=="both", it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind*='grid', *location*=None)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart*=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_timer\_event**(*name*, *loop*=None, *start*=None, *stop*=None, *period*=None, *timer*=None, *autostart*=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling `start()` method), start the timer as well.

**add\_to\_layout**(*element*, *location*=None, *kind*='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value*=None, *multivalued*=False, *add\_indicator*=True)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued*==True, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator*==True, add default indicator handler as well.

**change\_layout\_tags**(*add*=None, *remove*=None, *replace*=None)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**contained\_value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**get\_all\_indicators**()

Get indicator values of all widget in the container

**get\_all\_values**()

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name*=None)

Get indicator value for a widget with the given name (None means all indicators)

**get\_layout\_shape**(*name*=None)

Get shape (rows, cols) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**insert\_column**(*col, sublayout=None, stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row, sublayout=None, stretch=0*)

Insert a new row at the given location in the grid layout

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**iter\_sublayout\_items**(*name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested*==True, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info*==False, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info*==True, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element, location*)

Move the given layout element to a new location

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None, include='all', nested=True, tag=None, widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators**(*value, ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container



**set\_column\_stretch**(\*args, layout=None)

Set column stretch for a given layout.

Takes either two arguments **index** and **stretch**, or a single list of stretches for all columns.

**set\_indicator**(name, value, ignore\_missing=False)

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch**(\*args, layout=None)

Set row stretch for a given layout.

Takes either two arguments **index** and **stretch**, or a single list of stretches for all rows.

**set\_value**(name, value)

Set value of a widget with the given name (None means all values)

**setup\_name**(name)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(name)

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(name)

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**update\_indicators**()

Update all indicators to represent current values

**update\_value**(name=None)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is None, emit for all values in the table.

**using\_layout**(name)

Use a different sublayout as default inside the **with** block

**using\_layout\_tags**(add=None, remove=None, replace=None)

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout**(name, kind='grid', location=None)

Create a different sublayout and use it as default inside the **with** block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**class** pylablib.core.gui.widgets.container.QWidgetContainer(\*args, \*\*kwargs)

Bases: *IQWidgetContainer*, *object*

Generic widget container.

Combines *IQContainer* management of GUI values and timers with *QLayoutManagedWidget* management of the contained widget's layout.

Typically, adding widget adds them both to the container values and to the layout; however, this can be skipped by either using *QLayoutManagedWidget.add\_to\_layout()* (only add to the layout), or specifying *location="skip"* in *add\_child()* (only add to the container).

Simply a combination of *IQWidgetContainer* and *QWidget*.

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(name, widget, location=None, gui\_values\_path=True)

Add a contained child widget.

*name* specifies the child storage name; if *name==False*, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location=="skip"*, skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when *clear* or *remove\_child* methods are called; otherwise, simply its *clear* method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path=""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values**(name, widget, path, add\_change\_event=True)

Add child's values to the container's table.

If *widget* is a container and *path=""* or ends in *"/"* (e.g., *"subpath/"*), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event==True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_decoration\_label**(text, location='next', tag=None)

Add a decoration text label with the given text

**add\_frame**(name, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)

Add a new frame container to the layout.

*layout* specifies the layout (*"vbox"*, *"hbox"*, or *"grid"*) of the new frame, and *location* specifies its location within the container layout. If *no\_margins==True*, the frame will have no inner layout margins. The other parameters are the same as in *add\_child()* method.

**add\_group\_box**(name, caption, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout (*"vbox"*, *"hbox"*, or *"grid"*) of the new frame, and *location* specifies its location within the container layout. If *no\_margins==True*, the frame will have no inner layout margins. The other parameters are the same as in *add\_child()* method.

**add\_padding**(kind='auto', location='next', stretch=0, tag=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be *"vertical"*, *"horizontal"*, *"auto"* (vertical for *grid* and *vbox* layouts, horizontal for *hbox*), or *"both"* (stretches in both directions). If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**add\_spacer**(*height=0*, *width=0*, *stretch\_height=False*, *stretch\_width=False*, *stretch=0*, *location='next'*, *tag=None*)

Add a spacer with the given width and height to the given location.

If *stretch\_height==True* or *stretch\_width==True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind=="both"*, it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind='grid'*, *location=None*)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart==True* and the container has been started (by calling *start()* method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart==True* and the container has been started (by calling *start()* method), start the timer as well.

**add\_to\_layout**(*element*, *location=None*, *kind='widget'*)

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

**change\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace`* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear()**

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators()**

Get indicator values of all widget in the container

**get\_all\_values()**

Get values of all widget in the container

**get\_child(name)**

Get the child widget with the given name

**get\_element\_position(element)**

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.

**get\_handler(name)**

Get value handler of a widget with the given name

**get\_indicator(name=None)**

Get indicator value for a widget with the given name (None means all indicators)

**get\_layout\_shape(name=None)**

Get shape (rows, cols) of the current layout

**get\_layout\_tags()**

Get the set of currently applied layout tags

**get\_sublayout(name=None)**

Get the previously added sublayout

**get\_sublayout\_kind(name=None)**

Get the kind of the previously added sublayout

**get\_value(name=None)**

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal(name)**

Get a value-changed signal for a widget with the given name

**get\_widget(name)**

Get a widget corresponding to a value with the given name

**insert\_column(col, sublayout=None, stretch=0)**

Insert a new column at the given location in the grid layout

**insert\_row(row, sublayout=None, stretch=0)**

Insert a new row at the given location in the grid layout

**is\_running()**

Check if the container is running (started and not yet stopped)

**is\_stopping()**

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running(name)**

Check if the timer with the given name is running

**iter\_sublayout\_items(name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False)**

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested*==True, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info*==False, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info*==True, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element(element, location)**

Move the given layout element to a new location

**remove\_child(name, clear=True)**

Remove widget from the container and the layout and (if *clear*==True) clear it, and remove it

**remove\_layout\_element(element)**

Remove a previously added layout element

**remove\_sublayout\_items(name=None, include='all', nested=True, tag=None, widget\_action='remove')**

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators(value, ignore\_missing=True)****set\_all\_values(value)**

Set values of all widgets in the container

**set\_column\_stretch(\*args, layout=None)**

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_indicator(name, value, ignore\_missing=False)**

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch(\*args, layout=None)**

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_value(name, value)**

Set value of a widget with the given name (None means all values)

**setup(layout='vbox', no\_margins=False, name=None)**

Setup the layout.

**Parameters**

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(*name*)

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**update\_indicators**()

Update all indicators to represent current values

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is None, emit for all values in the table.

**using\_layout**(*name*)

Use a different sublayout as default inside the **with** block

**using\_layout\_tags**(*add=None, remove=None, replace=None*)

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout**(*name, kind='grid', location=None*)

Create a different sublayout and use it as default inside the **with** block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**class** pylablib.core.gui.widgets.container.QFrameContainer(*\*args, \*\*kwargs*)

Bases: [IQWidgetContainer](#), [object](#)

An extension of [IQWidgetContainer](#) for a QFrame Qt base class

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(*name, widget, location=None, gui\_values\_path=True*)

Add a contained child widget.

*name* specifies the child storage name; if *name==False*, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location=="skip"*, skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when **clear** or **remove\_child** methods are called; otherwise, simply its **clear** method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path*==*""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values**(*name*, *widget*, *path*, *add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path*==*""* or ends in *"/"* (e.g., *"subpath/"*), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. If *add\_change\_event*==*True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_decoration\_label**(*text*, *location*='next', *tag*=None)

Add a decoration text label with the given text

**add\_frame**(*name*, *layout*='vbox', *location*=None, *gui\_values\_path*=True, *no\_margins*=True)

Add a new frame container to the layout.

*layout* specifies the layout (*"vbox"*, *"hbox"*, or *"grid"*) of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==*True*, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_group\_box**(*name*, *caption*, *layout*='vbox', *location*=None, *gui\_values\_path*=True, *no\_margins*=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout (*"vbox"*, *"hbox"*, or *"grid"*) of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==*True*, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_padding**(*kind*='auto', *location*='next', *stretch*=0, *tag*=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be *"vertical"*, *"horizontal"*, *"auto"* (vertical for *grid* and *vbox* layouts, horizontal for *hbox*), or *"both"* (stretches in both directions). If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name*, *getter*=None, *setter*=None, *add\_indicator*=True)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator*==*True*, add default (stored value) indicator handler as well.

**add\_spacer**(*height*=0, *width*=0, *stretch\_height*=False, *stretch\_width*=False, *stretch*=0, *location*='next', *tag*=None)

Add a spacer with the given width and height to the given location.

If *stretch\_height*==*True* or *stretch\_width*==*True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*==*"both"*, it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind*='grid', *location*=None)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be *"grid"*, *"vbox"* (vertical single-column box), or *"hbox"* (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_to\_layout**(*element*, *location=None*, *kind='widget'*)

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

**change\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace`* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear()**

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators()**

Get indicator values of all widget in the container

**get\_all\_values()**

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.



**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (None means all indicators)

**get\_layout\_shape**(*name=None*)

Get shape (rows, cols) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**insert\_column**(*col, sublayout=None, stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row, sublayout=None, stretch=0*)

Insert a new row at the given location in the grid layout

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**iter\_sublayout\_items**(*name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element, location*)

Move the given layout element to a new location

**remove\_child**(*name, clear=True*)

Remove widget from the container and the layout and (if *clear==True*) clear it, and remove it

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None, include='all', nested=True, tag=None, widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators**(*value, ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**set\_column\_stretch**(*\*args, layout=None*)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_indicator**(*name, value, ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch**(*\*args, layout=None*)

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_value**(*name, value*)

Set value of a widget with the given name (None means all values)

**setup**(*layout='vbox', no\_margins=False, name=None*)

Setup the layout.

#### Parameters

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on **start()** method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(*name*)

Stop the timer with the given name (also called automatically on **stop()** method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

**using\_layout(name)**

Use a different sublayout as default inside the *with* block

**using\_layout\_tags(add=None, remove=None, replace=None)**

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout(name, kind='grid', location=None)**

Create a different sublayout and use it as default inside the *with* block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**class pylablib.core.gui.widgets.container.QDialogContainer(\*args, \*\*kwargs)**

Bases: [IQWidgetContainer](#), [object](#)

An extension of [IQWidgetContainer](#) for a QDialog Qt base class

**TimerUIDGenerator = <pylablib.core.utils.general.NamedUIDGenerator object>**

**add\_child(name, widget, location=None, gui\_values\_path=True)**

Add a contained child widget.

*name* specifies the child storage name; if *name*==*False*, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location*=="skip", skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when *clear* or *remove\_child* methods are called; otherwise, simply its *clear* method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path*=="") if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values(name, widget, path, add\_change\_event=True)**

Add child's values to the container's table.

If *widget* is a container and *path*==" or ends in "/"\* (e.g., "subpath/\*"), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event*==*True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_decoration\_label(text, location='next', tag=None)**

Add a decoration text label with the given text

**add\_frame(name, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)**

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==*True*, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_group\_box**(*name*, *caption*, *layout*='vbox', *location*=None, *gui\_values\_path*=True, *no\_margins*=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==True, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_padding**(*kind*='auto', *location*='next', *stretch*=0, *tag*=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name*, *getter*=None, *setter*=None, *add\_indicator*=True)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator*==True, add default (stored value) indicator handler as well.

**add\_spacer**(*height*=0, *width*=0, *stretch\_height*=False, *stretch\_width*=False, *stretch*=0, *location*='next', *tag*=None)

Add a spacer with the given width and height to the given location.

If *stretch\_height*==True or *stretch\_width*==True, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*=="both", it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind*='grid', *location*=None)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart*=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_timer\_event**(*name*, *loop*=None, *start*=None, *stop*=None, *period*=None, *timer*=None, *autostart*=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_to\_layout**(*element*, *location*=None, *kind*='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

**change\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace`* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear**()

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators**()

Get indicator values of all widget in the container

**get\_all\_values**()

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (*sublayout*, *location*), where *sublayout* is the sublayout name ("name" for the main layout), and *location* is a tuple (*row*, *column*, *rowspan*, *colspan*). If the given widget is not in this layout, return *None*.

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (*None* means all indicators)

**get\_layout\_shape**(*name=None*)

Get shape (*rows*, *cols*) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_value**(*name=None*)

Get value of a widget with the given name (*None* means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**insert\_column**(*col*, *sublayout=None*, *stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row*, *sublayout=None*, *stretch=0*)

Insert a new row at the given location in the grid layout

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**iter\_sublayout\_items**(*name=None*, *include=('widget',)*, *nested=False*, *tag=None*,  
*yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element*, *location*)

Move the given layout element to a new location

**remove\_child**(*name*, *clear=True*)

Remove widget from the container and the layout and (if *clear==True*) clear it, and remove it

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None*, *include='all'*, *nested=True*, *tag=None*, *widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators**(*value*, *ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**set\_column\_stretch**(\**args*, *layout=None*)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_indicator**(*name*, *value*, *ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch**(\**args*, *layout=None*)

Set row stretch for a given layout.

Takes either two arguments **index** and **stretch**, or a single list of stretches for all rows.

**set\_value**(*name*, *value*)

Set value of a widget with the given name (None means all values)

**setup**(*layout='vbox'*, *no\_margins=False*, *name=None*)

Setup the layout.

#### Parameters

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(*name*)

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**update\_indicators**()

Update all indicators to represent current values

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is None, emit for all values in the table.

**using\_layout**(*name*)

Use a different sublayout as default inside the **with** block

**using\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout**(*name*, *kind='grid'*, *location=None*)

Create a different sublayout and use it as default inside the **with** block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**class** pylablib.core.gui.widgets.container.QGroupBoxContainer(\*args, \*\*kwargs)

Bases: [IQWidgetContainer](#), [object](#)

An extension of [IQWidgetContainer](#) for a QGroupBox Qt base class

**setup**(caption=None, layout='vbox', no\_margins=False, name=None)

Setup the layout.

#### Parameters

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(name, widget, location=None, gui\_values\_path=True)

Add a contained child widget.

*name* specifies the child storage name; if *name*==False, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location*=="skip", skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when `clear` or `remove_child` methods are called; otherwise, simply its `clear` method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is False or None, do not add it to the GUI values table; if it is True, add it under the same root (*path*=="") if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values**(name, widget, path, add\_change\_event=True)

Add child's values to the container's table.

If *widget* is a container and *path*==" or ends in "/"\* (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event*==True, changing of the widget's value emits the container's `contained_value_changed` event

**add\_decoration\_label**(text, location='next', tag=None)

Add a decoration text label with the given text

**add\_frame**(name, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==True, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_group\_box**(name, caption, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins*==True, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_padding**(kind='auto', location='next', stretch=0, tag=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not None, it specifies stretch of the spacer the



corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**add\_spacer**(*height=0*, *width=0*, *stretch\_height=False*, *stretch\_width=False*, *stretch=0*, *location='next'*, *tag=None*)

Add a spacer with the given width and height to the given location.

If *stretch\_height==True* or *stretch\_width==True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind=="both"*, it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind='grid'*, *location=None*)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_to\_layout**(*element*, *location=None*, *kind='widget'*)

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

**change\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace`* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear()**

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators()**

Get indicator values of all widget in the container

**get\_all\_values()**

Get values of all widget in the container

**get\_child(name)**

Get the child widget with the given name

**get\_element\_position(element)**

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.

**get\_handler(name)**

Get value handler of a widget with the given name

**get\_indicator(name=None)**

Get indicator value for a widget with the given name (None means all indicators)

**get\_layout\_shape(name=None)**

Get shape (rows, cols) of the current layout

**get\_layout\_tags()**

Get the set of currently applied layout tags

**get\_sublayout(name=None)**

Get the previously added sublayout

**get\_sublayout\_kind(name=None)**

Get the kind of the previously added sublayout

**get\_value(name=None)**

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal(name)**

Get a value-changed signal for a widget with the given name

**get\_widget(name)**

Get a widget corresponding to a value with the given name

**insert\_column(col, sublayout=None, stretch=0)**

Insert a new column at the given location in the grid layout

**insert\_row(row, sublayout=None, stretch=0)**

Insert a new row at the given location in the grid layout

**is\_running()**

Check if the container is running (started and not yet stopped)

**is\_stopping()**

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running(name)**

Check if the timer with the given name is running

**iter\_sublayout\_items(name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False)**

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested*==True, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info*==False, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info*==True, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element(element, location)**

Move the given layout element to a new location

**remove\_child(name, clear=True)**

Remove widget from the container and the layout and (if *clear*==True) clear it, and remove it

**remove\_layout\_element(element)**

Remove a previously added layout element

**remove\_sublayout\_items(name=None, include='all', nested=True, tag=None, widget\_action='remove')**

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators(value, ignore\_missing=True)****set\_all\_values(value)**

Set values of all widgets in the container

**set\_column\_stretch(\*args, layout=None)**

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_indicator(name, value, ignore\_missing=False)**

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch(\*args, layout=None)**

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_value(name, value)**

Set value of a widget with the given name (None means all values)

**setup\_name(name)**

Set the object's name

**start()**

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer(name)**

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop()**

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer(name)**

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

**using\_layout(name)**

Use a different sublayout as default inside the **with** block

**using\_layout\_tags(add=None, remove=None, replace=None)**

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout(name, kind='grid', location=None)**

Create a different sublayout and use it as default inside the **with** block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**class** `pylablib.core.gui.widgets.container.QScrollAreaContainer(*args, name=None, **kwargs)`

Bases: [IQContainer](#), [object](#)

An extension of [IQWidgetContainer](#) for a QScrollArea Qt base class.

Due to Qt organization, this container is “intermediate”: it contains only a single [QWidgetContainer](#) widget (named "widget"), which in turn has all of the standard container traits: layout, multiple widgets, etc. Hence, when dealing with any container methods (adding children, changing layout, etc.), this widget (accessible with `.widget()` method) should be used.

**class** `QContainedWidget(*args, **kwargs)`

Bases: [QWidgetContainer](#)

**resizeEvent(event)**

**TimerUIDGenerator** = `<pylablib.core.utils.general.NamedUIDGenerator object>`

**add\_child(name, widget, location=None, gui\_values\_path=True)**

Add a contained child widget.

*name* specifies the child storage name; if *name*==False, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location*=="skip", skip adding it to the layout (can be manually added later). Note that if the

widget is added to the layout, it will be completely deleted when `clear` or `remove_child` methods are called; otherwise, simply its `clear` method will be called, and its GUI values will be deleted.

If `gui_values_path` is `False` or `None`, do not add it to the GUI values table; if it is `True`, add it under the same root (`path=""`) if it's a container, and under `name` if it's not; otherwise, `gui_values_path` specifies the path under which the widget values are stored.

**add\_child\_values**(*name, widget, path, add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path*=="" or ends in "/" (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if `add_change_event==True`, changing of the widget's value emits the container's `contained_value_changed` event

**add\_decoration\_label**(*text, location='next', tag=None*)

Add a decoration text label with the given text

**add\_frame**(*name, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True*)

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If `no_margins==True`, the frame will have no inner layout margins. The other parameters are the same as in `add_child()` method.

**add\_group\_box**(*name, caption, layout='vbox', location=None, gui\_values\_path=True, no\_margins=True*)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If `no_margins==True`, the frame will have no inner layout margins. The other parameters are the same as in `add_child()` method.

**add\_padding**(*kind='auto', location='next', stretch=0, tag=None*)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not `None`, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_property\_element**(*name, getter=None, setter=None, add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If `add_indicator==True`, add default (stored value) indicator handler as well.

**add\_spacer**(*height=0, width=0, stretch\_height=False, stretch\_width=False, stretch=0, location='next', tag=None*)

Add a spacer with the given width and height to the given location.

If `stretch_height==True` or `stretch_width==True`, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not `None`, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*=="both", it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(*name*, *kind*='grid', *location*=None)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_timer**(*name*, *period*, *autostart*=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_timer\_event**(*name*, *loop*=None, *start*=None, *stop*=None, *period*=None, *timer*=None, *autostart*=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_to\_layout**(*element*, *location*=None, *kind*='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_virtual\_element**(*name*, *value*=None, *multivalued*=False, *add\_indicator*=True)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued*==True, the internal value is assumed to be complex, so it is forced to be a [Dictionary](#) every time it is set. If *add\_indicator*==True, add default indicator handler as well.

**change\_layout\_tags**(*add*=None, *remove*=None, *replace*=None)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear()**

Clear the container.

All the timers are stopped, all the contained widgets are cleared and removed.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators()**

Get indicator values of all widget in the container

**get\_all\_values()**

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_element\_position(*element*)**

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.

**get\_handler(*name*)**

Get value handler of a widget with the given name

**get\_indicator(*name=None*)**

Get indicator value for a widget with the given name (None means all indicators)

**get\_layout\_shape(*name=None*)**

Get shape (rows, cols) of the current layout

**get\_layout\_tags()**

Get the set of currently applied layout tags

**get\_sublayout(*name=None*)**

Get the previously added sublayout

**get\_sublayout\_kind(*name=None*)**

Get the kind of the previously added sublayout

**get\_value(*name=None*)**

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal(*name*)**

Get a value-changed signal for a widget with the given name

**get\_widget(*name*)**

Get a widget corresponding to a value with the given name

**insert\_column(*col*, *sublayout=None*, *stretch=0*)**

Insert a new column at the given location in the grid layout

**insert\_row(*row*, *sublayout=None*, *stretch=0*)**

Insert a new row at the given location in the grid layout

**is\_running()**

Check if the container is running (started and not yet stopped)

**is\_stopping()**

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running(*name*)**

Check if the timer with the given name is running

**iter\_sublayout\_items(*name=None*, *include=('widget',)*, *nested=False*, *tag=None*, *yield\_layout\_info=False*)**

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (kind, element), where kind can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (kind, element, layout, index), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element*, *location*)

Move the given layout element to a new location

**remove\_child**(*name*, *clear=True*)

Remove widget from the container and the layout and (if *clear==True*) clear it, and remove it

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None*, *include='all'*, *nested=True*, *tag=None*,  
*widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_all\_indicators**(*value*, *ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**set\_column\_stretch**(\**args*, *layout=None*)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_indicator**(*name*, *value*, *ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch**(\**args*, *layout=None*)

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_value**(*name*, *value*)

Set value of a widget with the given name (None means all values)

**setup**(*layout='vbox'*, *no\_margins=False*, *name=None*)

Setup the layout.

#### Parameters

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls *start* method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on *start()* method)



**stop()**

Stop the container.

Stops all the internal timers, and calls `stop` method for all the contained widgets.

**stop\_timer(name)**

Stop the timer with the given name (also called automatically on `stop()` method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is None, emit for all values in the table.

**using\_layout(name)**

Use a different sublayout as default inside the `with` block

**using\_layout\_tags(add=None, remove=None, replace=None)**

Context manager for temporarily using different layout tags.

See `change_layout_tags()` for details.

**using\_new\_sublayout(name, kind='grid', location=None)**

Create a different sublayout and use it as default inside the `with` block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**setup(layout='vbox', no\_margins=False, name=None, fix\_width=True, fix\_height=False)**

Setup the container.

*layout* specifies the container layout, *no\_margins* determines whether margins within the container are removed, *name* specifies the widget name (if not specified yet). *fix\_width* and *fix\_height* determine whether the corresponding direction behaves as a scroll window (i.e., the size is fixed when the content changes), or as a standard widget container (the size is determined by the content).

**clear()**

Clear the container.

Stop all timers and widgets, and call `clear` methods of all contained widgets, remove all widgets from the values table, remove all widgets from the table.

**TimerUIDGenerator = <pylablib.core.utils.general.NamedUIDGenerator object>**

**add\_child(name, widget, gui\_values\_path=True, add\_change\_event=True)**

Add a contained child widget.

If *gui\_values\_path* is False or None, do not add it to the GUI values table; if it is True, add it under the same root (*path*=="" ) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored. if *add\_change\_event*==True, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_child\_values(name, widget, path, add\_change\_event=True)**

Add child's values to the container's table.

If *widget* is a container and *path*=="" or ends in "/"\* (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event*==True, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators**()

Get indicator values of all widget in the container

**get\_all\_values**()

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (*None* means all indicators)

**get\_value**(*name=None*)

Get value of a widget with the given name (*None* means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**is\_running()**

Check if the container is running (started and not yet stopped)

**is\_stopping()**

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running(name)**

Check if the timer with the given name is running

**remove\_child(name, clear=True)**

Remove child from the container and (if `clear==True`) clear it

**set\_all\_indicators(value, ignore\_missing=True)****set\_all\_values(value)**

Set values of all widgets in the container

**set\_indicator(name, value, ignore\_missing=False)**

Set indicator value for a widget or a branch with the given name

**set\_value(name, value)**

Set value of a widget with the given name (None means all values)

**setup\_name(name)**

Set the object's name

**start()**

Start the container.

Starts all the internal timers, and calls `start` method for all the contained widgets.

**start\_timer(name)**

Start the timer with the given name (also called automatically on `start()` method)

**stop()**

Stop the container.

Stops all the internal timers, and calls `stop` method for all the contained widgets.

**stop\_timer(name)**

Stop the timer with the given name (also called automatically on `stop()` method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If `name` is None, emit for all values in the table.

**class** pylablib.core.gui.widgets.container.QTabContainer(\*args, \*\*kwargs)

Bases: [IQContainer](#), [object](#)

Container which manages tab widget.

Does not have its own layout, but can add or remove tabs, which are represented as [QFrameContainer](#) widgets.

**add\_tab**(*name*, *caption*, *index=None*, *widget=None*, *layout='vbox'*, *gui\_values\_path=True*, *no\_margins=True*)

Add a new tab container with the given *caption* to the widget.

*index* specifies the new tab's index (*None* means adding to the end, negative values count from the end). If *widget* is *None*, create a new frame widget using the given *layout* ("vbox", "hbox", or "grid") and *no\_margins* (specifies whether the frame has inner margins) arguments; otherwise, use the supplied widget. The other parameters are the same as in [add\\_child\(\)](#) method.

**remove\_tab**(*name*)

Remove a tab with the given name.

Clear it, remove its GUI values, and delete it and all contained widgets.

**hide\_tab**(*name*, *hide=True*)

Hide or show a tab with the given name

**clear**()

Clear the container.

Stop all timers and widgets, and call **clear** methods of all contained widgets, remove all widgets from the values table, remove all widgets from the table.

**get\_current\_name**()

Get current tab name

**set\_by\_name**(*name*)

Set tab by name

**get\_index\_by\_name**(*name*)

Get index by the tab's name

**get\_name\_by\_index**(*idx*)

Return the name of the tab at a given index, or *None* if this tab is not being tracked

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(*name*, *widget*, *gui\_values\_path=True*, *add\_change\_event=True*)

Add a contained child widget.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path=""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored. if *add\_change\_event==True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_child\_values**(*name*, *widget*, *path*, *add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path=""* or ends in *"/"* (e.g., *"subpath/"*), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event==True*, changing of the widget's value emits the container's *contained\_value\_changed* event

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**add\_timer**(*name*, *period*, *autostart=True*)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop=None*, *start=None*, *stop=None*, *period=None*, *timer=None*, *autostart=True*)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart==True* and the container has been started (by calling `start()` method), start the timer as well.

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. If *add\_indicator==True*, add default indicator handler as well.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators**()

Get indicator values of all widget in the container

**get\_all\_values**()

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (None means all indicators)

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**remove\_child**(*name*, *clear=True*)

Remove child from the container and (if *clear==True*) clear it

**set\_all\_indicators**(*value*, *ignore\_missing=True*)

**set\_all\_values**(*value*)

Set values of all widgets in the container

**set\_indicator**(*name*, *value*, *ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_value**(*name*, *value*)

Set value of a widget with the given name (None means all values)

**setup**(*name=None*)

Setup the container by initializing its GUI values and setting the *ctl* attribute

**setup\_name**(*name*)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(*name*)

Start the timer with the given name (also called automatically on **start()** method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(*name*)

Stop the timer with the given name (also called automatically on **stop()** method)

**update\_indicators**()

Update all indicators to represent current values

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

## pylablib.core.gui.widgets.edit module

**class** pylablib.core.gui.widgets.edit.**TextEdit**(*parent*, *value=None*)

Bases: **object**

Expanded text edit.

Maintains internally stored consistent value (which can be, e.g., accessed from different threads).

**keyPressEvent**(*event*)

**set\_expandable**(*left=0, right=0, top=0, bottom=0*)

Make text edit expandable.

If it is expandable, the edit size is expanded by the given size into the corresponding directions. If all are zero, the widget behaves as normal.

**focusInEvent**(*evt*)

**focusOutEvent**(*evt*)

**value\_entered** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is entered (regardless of whether it stayed the same)

**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value**()

Get current text value

**show\_value**(*interrupt\_edit=False*)

Display currently stored text value

If *interrupt\_edit*==True and the edit is currently being modified by the user, don't update the display.

**set\_value**(*value, notify\_value\_change=True, interrupt\_edit=False*)

Set current text value.

If *notify\_value\_change*==True, emit the *value\_changed* signal; otherwise, change value silently. If *interrupt\_edit*==True and the edit is currently being modified by the user, don't update the display (but still update the internally stored value).

**class** `pylablib.core.gui.widgets.edit.NumEdit`(*parent, value=None, limiter=None, formatter=None, custom\_steps=None*)

Bases: `object`

Labview-style numerical edit.

Maintains internally stored consistent value (which can be, e.g., accessed from different threads). Supports different number representations, metric prefixes (in input or output), keyboard shortcuts (up/down for changing number, escape for cancelling).

#### Parameters

- **parent** – parent widget
- **value** – initial value (None means no value is set)
- **limiter** – number limiter (for details, see `set_limiter()`)
- **formatter** – number formatter (for details, see `set_formatter()`)
- **custom\_steps** – if not None, can specify custom fixed value steps when up/down keys are pressed with a modifier key (Control, Alt, or Shift) specifies a dictionary `{'ctrl':ctrl_step, 'alt':alt_step, 'shift':shift_step}` with the corresponding steps (missing elements mean that the modifier key is ignored)

**keyPressEvent**(*event*)

**set\_limiter**(*limiter*, *new\_value=None*)

Change current numerical limiter.

Limiter can be a callable object which takes a single value and either returns a limited value, or raises `limiter.LimitError` if it should be ignored; or it can be a tuple (`lower`, `upper`, `action`, `value_type`), where `lower` and `upper` are the limits (`None` means no limits), `action` defines out-of-limit action (either "ignore" to ignore entered value, or "coerce" to truncate to the nearest limit), and `value_type` can be `None` (keep value as is), "float" (cast value to float), "int" (cast value to int). If the tuple is shorter, the missing parts are filled by default values (`None`, `None`, "ignore", `None`).

**set\_formatter**(*formatter*)

Change current numerical formatter.

Formatter can be a callable object turning value into a string, a string ("float", "int", or a format string, e.g., ".5f"), or a tuple starting with "float" which contains arguments to the `formatter.FloatFormatter`.

**set\_float\_formatter**(*output\_format='auto'*, *digits=9*, *add\_trailing\_zeros=True*, *leading\_zeros=0*, *explicit\_sign=False*)

Set up float formatter.

Has the same functionality as `set_formatter()` (i.e., `set_float_formatter(*args)` is equivalent to `set_formatter(("float",)+args)`), but explicitly lists the arguments.

#### Parameters

- **output\_format** (*str*) – can be "auto" (use standard Python conversion), "SI" (use SI prefixes if possible), or "sci" (scientific "E" notation).
- **digits** (*int*) – if `add_trailing_zeros==False`, determines the number of significant digits; otherwise, determines precision (number of digits after decimal point).
- **add\_trailing\_zeros** (*bool*) – if `True`, always show fixed number of digits after the decimal point, with zero padding if necessary.
- **leading\_zeros** (*bool*) – determines the minimal size of the integer part (before the decimal point) of the number; pads with zeros if necessary.
- **explicit\_sign** (*bool*) – if `True`, always add explicit plus sign.

**set\_custom\_steps**(*custom\_steps=None*)

Specify custom fixed value steps when up/down keys are pressed with a modifier key (Control, Alt, or Shift).

*custom\_steps* is a dictionary {'ctrl':ctrl\_step, 'alt':alt\_step, 'shift':shift\_step} with the corresponding steps (missing elements mean that the modifier key is ignored).

**get\_cursor\_order**()

Get a decimal order of the text cursor

**set\_cursor\_order**(*order*)

Move text cursor to a given decimal order

**repr\_value**(*value*)

Return representation of *value* according to the current numerical format

**value\_entered** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is entered (regardless of whether it stayed the same)



**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value()**

Get current numerical value

**show\_value**(*interrupt\_edit=False, preserve\_cursor\_order=True*)

Display currently stored numerical value

If *interrupt\_edit*==False and the edit is currently being modified by the user, don't update the display. If *preserve\_cursor\_order*==True and the display value is being edited, keep the decimal order of the cursor position after change.

**set\_value**(*value, notify\_value\_change=True, interrupt\_edit=False, preserve\_cursor\_order=True*)

Set and display current numerical value.

If *notify\_value\_change*==True, emit the *value\_changed* signal; otherwise, change value silently. If *interrupt\_edit*==False and the edit is currently being modified by the user, don't update the display (but still update the internally stored value). If *preserve\_cursor\_order*==True and the display value is being edited, keep the decimal order of the cursor position after change.

## pylablib.core.gui.widgets.label module

**class** pylablib.core.gui.widgets.label.**TextLabel**(*parent, value=None*)

Bases: `object`

Labview-style text label.

The main difference from the standard `QLabel` is the changed event.

**clicked** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**mousePressEvent**(*ev*)

**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value()**

Get current numerical value

**set\_value**(*value*)

Set and display current text value

**class** pylablib.core.gui.widgets.label.**EnumLabel**(*parent, options, value=None, prep=None, styles=None, default\_style=""*)

Bases: `object`

Labview-style label for enumerated values.

Can automatically convert input enum values into corresponding text labels based on the *options* dictionary. Can also specify a function which takes a single value argument and converts into a enum value before checking *options*; useful for “fuzzy” options (e.g., when 0 and False mean the same thing)

**clicked** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**mousePressEvent**(*ev*)

**set\_out\_of\_range**(*action='error'*)

Set behavior when out-of-range value is applied.

Can be "error" (raise error), "text" (turn value into text and display it), or "ignore" (keep current value).

**set\_options**(*options, value=None, index=None*)

Set new set of options.

If *index\_values* is not `None`, set these as the new index values; otherwise, index values are reset. If *options* is a dictionary, interpret it as a mapping {*option*: *index\_value*}. If *value* is specified, set as the new values. If *index* is specified, use it as the index of a new value; if both *value* and *index* are specified, the *value* takes priority.

**set\_styles**(*styles=None, default\_style=""*)

Set the dictionary of styles {*value*: *style*} and the default style

**value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

Signal emitted when value is changed

**get\_value**()

Get current numerical value

**set\_value**(*value*)

Set and display current text value

**repr\_value**(*value*)

Return representation of *value* as a combo box text

**class** pylablib.core.gui.widgets.label.**NumLabel**(*parent, value=None, limiter=None, formatter=None, allow\_text=True*)

Bases: `object`

Labview-style numerical label.

Supports different number representations and metric prefixes.

#### Parameters

- **parent** – parent widget
- **value** – initial value (`None` means no value is set)
- **limiter** – number limiter (for details, see `set_limiter()`)
- **formatter** – number formatter (for details, see `set_formatter()`)
- **allow\_text** – if `True`, can also take text values (which are displayed as is); otherwise, raise an error.

**clicked** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**mousePressEvent**(*ev*)

**set\_limiter**(*limiter, new\_value=None*)

Change current numerical limiter.

Limiter can be a callable object which takes a single value and either returns a limited value, or raises `limiter.LimitError` if it should be ignored; or it can be a tuple (*lower*, *upper*, *action*, *value\_type*), where *lower* and *upper* are the limits (`None` means no limits), *action* defines out-of-limit action (either "ignore" to ignore entered value, or "coerce" to truncate to the nearest limit), and

`value_type` can be `None` (keep value as is), `"float"` (cast value to float), `"int"` (cast value to int). If the tuple is shorter, the missing parts are filled by default values (`None`, `None`, `"ignore"`, `None`).

**set\_formatter(formatter)**

Change current numerical formatter.

Formatter can be a callable object turning value into a string, a string (`"float"`, `"int"`, or a format string, e.g., `".5f"`), or a tuple starting with `"float"` which contains arguments to the [formatter.FloatFormatter](#).

**set\_float\_formatter(output\_format='auto', digits=9, add\_trailing\_zeros=True, leading\_zeros=0, explicit\_sign=False)**

Set up float formatter.

Has the same functionality as [set\\_formatter\(\)](#) (i.e., `set_float_formatter(*args)` is equivalent to `set_formatter(("float",)+args)`), but explicitly lists the arguments.

#### Parameters

- **output\_format** (*str*) – can be `"auto"` (use standard Python conversion), `"SI"` (use SI prefixes if possible), or `"sci"` (scientific “E” notation).
- **digits** (*int*) – if `add_trailing_zeros==False`, determines the number of significant digits; otherwise, determines precision (number of digits after decimal point).
- **add\_trailing\_zeros** (*bool*) – if `True`, always show fixed number of digits after the decimal point, with zero padding if necessary.
- **leading\_zeros** (*bool*) – determines the minimal size of the integer part (before the decimal point) of the number; pads with zeros if necessary.
- **explicit\_sign** (*bool*) – if `True`, always add explicit plus sign.

**repr\_value(value)**

Return representation of *value* according to the current numerical format

**value\_changed** = `<Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>`

Signal emitted when value is changed

**get\_value()**

Get current numerical value

**set\_value(value)**

Set and display current numerical value

## pylablib.core.gui.widgets.layout\_manager module

**class** `pylablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget(*args, **kwargs)`

Bases: `object`

GUI widget which can manage layouts.

Typically, first it is set up using [setup\(\)](#) method to specify the master layout kind; afterwards, widgets and sublayout can be added using [add\\_to\\_layout\(\)](#). In addition, it can directly add named sublayouts using [add\\_sublayout\(\)](#) method.

Abstract mix-in class, which needs to be added to a class inheriting from `QWidget`. Alternatively, one can directly use [QLayoutManagedWidget](#), which already inherits from `QWidget`.

**setup**(*layout='grid', no\_margins=False*)

Setup the layout.

**Parameters**

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).
- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**using\_layout**(*name*)

Use a different sublayout as default inside the `with` block

**change\_layout\_tags**(*add=None, remove=None, replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**get\_layout\_tags**()

Get the set of currently applied layout tags

**using\_layout\_tags**(*add=None, remove=None, replace=None*)

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**add\_to\_layout**(*element, location=None, kind='widget'*)

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (*sublayout*, *location*), where *sublayout* is the sublayout name ("name" for the main layout), and *location* is a tuple (*row*, *column*, *rowspan*, *colspan*). If the given widget is not in this layout, return None.

**move\_layout\_element**(*element, location*)

Move the given layout element to a new location

**add\_sublayout**(*name, kind='grid', location=None*)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**using\_new\_sublayout**(*name, kind='grid', location=None*)

Create a different sublayout and use it as default inside the `with` block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**iter\_sublayout\_items**(*name=None, include=('widget'), nested=False, tag=None, yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**remove\_sublayout\_items**(*name=None, include='all', nested=True, tag=None, widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_layout\_shape**(*name=None*)

Get shape (*rows*, *cols*) of the current layout

**add\_spacer**(*height=0, width=0, stretch\_height=False, stretch\_width=False, stretch=0, location='next', tag=None*)

Add a spacer with the given width and height to the given location.

If *stretch\_height==True* or *stretch\_width==True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind=="both"*, it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_padding**(*kind='auto', location='next', stretch=0, tag=None*)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**set\_row\_stretch**(\**args, layout=None*)

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_column\_stretch**(\**args, layout=None*)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**add\_decoration\_label**(*text, location='next', tag=None*)

Add a decoration text label with the given text

**insert\_row**(*row, sublayout=None, stretch=0*)

Insert a new row at the given location in the grid layout

**insert\_column**(*col, sublayout=None, stretch=0*)

Insert a new column at the given location in the grid layout

**clear()**

Clear the layout and remove all the added elements

**class** pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget(\*args, \*\*kwargs)

Bases: *IQLayoutManagedWidget*, *object*

GUI widget which can manage layouts.

Typically, first it is set up using *setup()* method to specify the master layout kind; afterwards, widgets and sublayout can be added using *add\_to\_layout()*. In addition, it can directly add named sublayouts using *add\_sublayout()* method.

Simply a combination of *IQLayoutManagedWidget* and *QWidget*.

**add\_decoration\_label**(text, location='next', tag=None)

Add a decoration text label with the given text

**add\_padding**(kind='auto', location='next', stretch=0, tag=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for *grid* and *vbox* layouts, horizontal for *hbox*), or "both" (stretches in both directions). If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_spacer**(height=0, width=0, stretch\_height=False, stretch\_width=False, stretch=0, location='next', tag=None)

Add a spacer with the given width and height to the given location.

If *stretch\_height*==*True* or *stretch\_width*==*True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not *None*, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*=="both", it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_sublayout**(name, kind='grid', location=None)

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_to\_layout**(element, location=None, kind='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**change\_layout\_tags**(add=None, remove=None, replace=None)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear()**

Clear the layout and remove all the added elements

**get\_element\_position**(element)

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return *None*.

**get\_layout\_shape**(*name=None*)

Get shape (rows, cols) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**insert\_column**(*col, sublayout=None, stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row, sublayout=None, stretch=0*)

Insert a new row at the given location in the grid layout

**iter\_sublayout\_items**(*name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (*kind*, *element*), where *kind* can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (*kind*, *element*, *layout*, *index*), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element, location*)

Move the given layout element to a new location

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None, include='all', nested=True, tag=None, widget\_action='remove')*

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_column\_stretch**(*\*args, layout=None*)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_row\_stretch**(*\*args, layout=None*)

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**setup**(*layout='grid', no\_margins=False*)

Setup the layout.

#### Parameters

- **layout** – layout kind; can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

- **no\_margins** – if True, set all layout margins to zero (useful when the widget is in the middle of layout hierarchy)

**using\_layout**(*name*)

Use a different sublayout as default inside the `with` block

**using\_layout\_tags**(*add=None, remove=None, replace=None*)

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout**(*name, kind='grid', location=None*)

Create a different sublayout and use it as default inside the `with` block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

## pylablib.core.gui.widgets.param\_table module

**class** `pylablib.core.gui.widgets.param_table.ParamTable`(*parent=None, name=None*)

Bases: [QWidgetContainer](#)

GUI parameter table.

Simplifies creating code-generated controls and displays table layouts.

Has methods for adding various kinds of controls (labels, edit boxes, combo boxes, check boxes), automatically creates values table for easy settings/getting. By default supports 2-column (label-control) and 3-column (label-control-indicator) layout, depending on the parameters given to [setup\(\)](#).

Similar to [GUIValues](#), has three container-like accessor: `.h` for getting the value handler (i.e., `self.get_handler(name)` is equivalent to `self.h[name]`), `.w` for getting the underlying widget (i.e., `self.get_widget(name)` is equivalent to `self.w[name]`), `.v` for settings/getting values using the default getting method (equivalent to `.wv` if `cache_values=False` in [setup\(\)](#), and to `.cv` otherwise), `.wv` for settings/getting current current widget values without caching (i.e., `self.get_value(name)` is equivalent to `self.v[name]`, and `self.set_value(name, value)` is equivalent to `self.v[name]=value`), `.cv` for settings/getting values using cached value's table for getting (i.e., `self.current_values[name]` is equivalent to `self.cv[name]`, and `self.set_value(name, value)` is equivalent to `self.cv[name]=value`), (i.e., `self.get_value(name)` is equivalent to `self.v[name]`, and `self.set_value(name, value)` is equivalent to `self.v[name]=value`), `.i` for settings/getting indicator values (i.e., `self.get_indicator(name)` is equivalent to `self.i[name]`, and `self.set_indicator(name, value)` is equivalent to `self.i[name]=value`) `.vs` for getting the value changed Qt signal (i.e., `self.get_value_changed_signal(name)` is equivalent to `self.s[name]`),

Like most widgets, requires calling [setup\(\)](#) to set up before usage.

### Parameters

**parent** – parent widget

**setup**(*name=None, add\_indicator=True, gui\_thread\_safe=False, cache\_values=False, change\_focused\_control=False*)

Setup the table.

### Parameters

- **name** (*str*) – table widget name
- **add\_indicator** (*bool*) – if True, add indicators for all added widgets by default.



- **gui\_thread\_safe** (*bool*) – if True, all value-access and indicator-access calls (`get/set_value`, `get/set_all_values`, `get/set_indicator`, and `update_indicators`) are automatically called in the GUI thread.
- **cache\_values** (*bool*) – if True or "update\_one", store a dictionary with all the current values and update it every time a GUI value is changed; provides a thread-safe way to check current parameters without lag (unlike `get_value()` or `get_all_values()` with `gui_thread_safe==True`, which re-route calls to a GUI thread and may cause up to 100ms delay) can also be set to "update\_all", in which case change of any value will cause value update of all variables; otherwise, change of a value will only cause update of that same value (might potentially miss some value updates for custom controls).
- **change\_focused\_control** (*bool*) – if False and `set_value()` method is called while the widget has user focus, ignore the value; note that `set_all_values()` will still set the widget value.

**add\_sublayout**(*name*, *kind*='grid', *location*=('next', 0, 1, 'end'))

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**using\_new\_sublayout**(*name*, *kind*='grid', *location*=('next', 0, 1, 'end'))

Create a different sublayout and use it as default inside the `with` block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**pad\_borders**(*kind*='both', *stretch*=0)

Add expandable paddings on the bottom and/or right border.

*kind* can be "bottom", "right", "both", or "none" (do nothing). Note that if more elements are added, they will be placed after the padding, so the table will be padded in the middle.

**add\_frame**(*name*, *layout*='vbox', *location*=('next', 0, 1, 'end'), *gui\_values\_path*=True, *no\_margins*=True)

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If `no_margins==True`, the frame will have no inner layout margins. The other parameters are the same as in `add_child()` method.

**add\_group\_box**(*name*, *caption*, *layout*='vbox', *location*=('next', 0, 1, 'end'), *gui\_values\_path*=True, *no\_margins*=True)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If `no_margins==True`, the frame will have no inner layout margins. The other parameters are the same as in `add_child()` method.

**class ParamRow**(*widget*, *label*, *indicator*, *value\_handler*, *indicator\_handler*)

Bases: `tuple`

**indicator**

**indicator\_handler**

**label**

**value\_handler**

**widget**

**add\_simple\_widget**(*name*, *widget*, *label*=None, *value\_handler*=None, *add\_indicator*=None, *location*=None, *tooltip*=None, *add\_change\_event*=True)

Add a ‘simple’ (single-spaced, single-valued) widget to the table.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **widget** – widget to add
- **label** (*str*) – if not None, specifies label to put in front of the widget in the layout
- **value\_handler** – value handler of the widget; by default, use auto-detected value handler (works for many simple built-in or custom widgets)
- **add\_indicator** – if True, add an indicator label in the third column and a corresponding indicator handler in the built-in values table; by default, use the default value supplied to *setup()*
- **location** (*tuple*) – tuple (row, column) specifying location of the widget (or widget label, if it is specified); by default, add to a new row in the end and into the first column can also be a string "skip", which means that the widget is added to some other location manually later (this option only works if *label*=None, and doesn't add any indicator)
- **tooltip** – widget tooltip (mouseover text)
- **add\_change\_event** (*bool*) – if True, changing of the widget's value emits the table's *contained\_value\_changed* event

Return the widget's value handler

**add\_custom\_widget**(*name*, *widget*, *value\_handler*=None, *indicator\_handler*=None, *location*=None, *tooltip*=None, *add\_change\_event*=True)

Add a ‘custom’ (multi-spaced, possibly complex-valued) widget to the table.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **widget** – widget to add
- **value\_handler** – value handler of the widget; by default, use auto-detected value handler (works for many simple built-in or custom widgets)
- **indicator\_handler** – indicator handler of the widget; by default, use auto-detected indicator handler (use *set/get\_indicator* methods if present, or no indicator otherwise)
- **location** (*tuple*) – tuple (row, column, rowspan, colspan) specifying location of the widget; by default, add to a new row in the end and into the first column, span one row and all table columns can also be a string "skip", which means that the widget is added to some other location manually later
- **add\_change\_event** (*bool*) – if True, changing of the widget's value emits the table's *contained\_value\_changed* event

Return the widget's value handler

**remove\_widget**(*name*)

Remove the widget and, if applicable, its indicator and label

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *on\_set\_value='store'*, *signal\_kind='none'*, *add\_indicator=None*)

Add a virtual table element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. *on\_set\_value* specifies the behavior when value is set; can be "store" (store as the current value and return on *get\_value* later) or "ignore" (keep the original value) *signal\_kind* specifies value changed signal kind; can be "none" (no signal), "direct" (emulation of direct-connection signal, which is called whenever the value changes), or "dummy" (emulation of direct-connection signal, which is never called). If *add\_indicator==True*, add default indicator handler as well.

**add\_property\_element**(*name*, *getter=None*, *setter=None*, *add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator==True*, add default (stored value) indicator handler as well.

**add\_button**(*name*, *caption*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a button to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str*) – text on the button
- **virtual** (*bool*) – if *True*, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as *add\_simple\_widget()*.

**add\_toggle\_button**(*name*, *caption*, *value=False*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a toggle button to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str* or *list*) – text on the button; can be a single string, or a list of two strings which specifies the caption for off and on states
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if *True*, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as *add\_simple\_widget()*.

**add\_dropdown\_button**(*name*, *caption*, *options=None*, *index\_values=None*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a button which shows a dropdown menu when clicked.

Similar in behavior to a regular button, but its changed event provides a single argument which is the name of the selected item.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str* or *list*) – text on the button
- **options** (*list*) – list of strings specifying menu options
- **index\_values** (*list*) – list of values corresponding to menu options; if supplied, these values are used when setting/getting values or sending signals.
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_check\_box**(*name*, *caption*, *value=False*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a checkbox to the table.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str*) – text on the checkbox
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_text\_label**(*name*, *value=""*, *label=None*, *location=None*, *tooltip=None*, *add\_change\_event=False*, *virtual=False*)

Add a text label to the table.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_enum\_label**(*name*, *options*, *value=None*, *out\_of\_range='error'*, *prep=None*, *styles=None*, *label=None*, *location=None*, *tooltip=None*, *add\_change\_event=False*, *virtual=False*)

Add a text label to the table.

**Parameters**

- **name** (*str*) – widget name (used to reference its value in the values table)
- **options** (*dict*) – dictionary {*index\_value*: *text*} which converts values into text
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "text" (convert value into text), or "ignore" (keep current value).
- **prep** – a function which takes a single value argument and converts into an option; useful for “fuzzy” options (e.g., when 0 and False mean the same thing)

- **styles** – a dictionary {value: style} which defines stylesheet styles based on the value (if some values are not in the dictionary, use default no-style value)
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

```
add_style_indicator_label(name, caption, options=(True, False), value=False, out_of_range='error',
    prep=<class 'bool'>, styles=None, label=None, location=None,
    tooltip=None, add_change_event=False, virtual=False)
```

Add a label to the table with a fixed caption but whose style indicates the value.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** – text on the label
- **options** (*list*) – list with the possible values
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "text" (convert value into text), or "ignore" (keep current value).
- **prep** – a function which takes a single value argument and converts into an option; useful for “fuzzy” options (e.g., when 0 and False mean the same thing)
- **styles** – a dictionary {value: style} which defines stylesheet styles based on the value (if some values are not in the dictionary, use default no-style value); can be a single string value, which gets assigned to True value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

```
add_num_label(name, value=0, limiter=None, formatter=None, label=None, tooltip=None, location=None,
    add_change_event=False, virtual=False)
```

Add a numerical label to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*float*) – specifies initial value
- **limiter** (*tuple*) – tuple (upper\_limit, lower\_limit, action, value\_type) specifying value limits; see [limiter.as\\_limiter\(\)](#) for details
- **formatter** (*tuple*) – either "int" (for integer values), or tuple specifying floating value format; see [formatter.as\\_formatter\(\)](#) for details
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

```
add_text_edit(name, value="", label=None, multiline=False, add_indicator=None, location=None,
    tooltip=None, add_change_event=True, virtual=False)
```

Add a text edit to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)

- **value** (*bool*) – specifies initial value
- **multiline** (*bool*) – if True, use multi-line text edit widget; otherwise, use a standard single-line edit
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_num\_edit**(*name*, *value=None*, *limiter=None*, *formatter=None*, *custom\_steps=None*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a numerical edit to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **limiter** (*tuple*) – tuple (upper\_limit, lower\_limit, action, value\_type) specifying value limits; see [NumEdit.set\\_limiter\(\)](#) for details
- **formatter** (*tuple*) – either "int" (for integer values), or tuple specifying floating value format; see [NumEdit.set\\_formatter\(\)](#) for details
- **custom\_steps** – if not None, can specify custom fixed value steps when up/down keys are pressed with a modifier key (Control, Alt, or Shift) specifies a dictionary {'ctrl':ctrl\_step, 'alt':alt\_step, 'shift':shift\_step} with the corresponding steps (missing elements mean that the modifier key is ignored)
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_progress\_bar**(*name*, *value=None*, *label=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a progress bar to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_combo\_box**(*name*, *value=None*, *options=None*, *index\_values=None*, *out\_of\_range='reset'*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a combo box to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** – specifies initial value
- **options** (*list*) – list of strings specifying box options or a dictionary {option: index\_value}

- **index\_values** (*list*) – list of values corresponding to box options; if supplied, these values are used when setting/getting values or sending signals; if *options* is a dictionary, this parameter is ignored
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "reset" (reset to no-value position), or "ignore" (keep current value).
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_button\_selector**(*name*, *value=None*, *options=None*, *index\_values=None*, *out\_of\_range='reset'*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a combo box to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** – specifies initial value
- **options** (*list*) – list of strings specifying box options or a dictionary {option: index\_value}
- **index\_values** (*list*) – list of values corresponding to box options; if supplied, these values are used when setting/getting values or sending signals; if *options* is a dictionary, this parameter is ignored
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "reset" (reset to no-value position), or "ignore" (keep current value).
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**set\_enabled**(*names=None*, *enabled=True*, *include\_indicator=True*, *include\_label=True*)

Enable or disable widgets with the given names (by default, all widgets)

**set\_visible**(*names=None*, *visible=True*, *include\_indicator=True*, *include\_label=True*)

Show or hide widgets with the given names (by default, all widgets)

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_all\_values**()

Get values of all widget in the container

**set\_value**(*name*, *value*, *force=True*)

Set value of a widget with the given name.

If *force==True*, force widget value (e.g., ignoring restriction on not changing values of focused widgets)

**set\_all\_values**(*value*, *force=True*)

Set values of all widgets in the table.

If *force==True*, force widget value (e.g., ignoring restriction on not changing values of focused widgets)

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**get\_indicator\_widget**(*name*)

Get indicator widget for a parameter with the given name, or *None* if this parameter has no indicator label

**get\_label\_widget**(*name*)

Get label widget for a parameter with the given name, or *None* if this parameter has no label

**get\_child**(*name*)

Get the child widget with the given name

**remove\_child**(*name, clear=True*)

Remove widget from the container and the layout and (if *clear==True*) clear it, and remove it

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (*None* means all indicators)

**get\_all\_indicators**()

Get indicator values of all widget in the container

**set\_indicator**(*name, value, ignore\_missing=False*)

Set indicator value for a widget or a branch with the given name

**set\_all\_indicators**(*value, ignore\_missing=True*)

**update\_indicators**()

Update all indicators to represent current values

**clear**(*disconnect=False*)

Clear the table (remove all widgets)

If *disconnect==True*, also disconnect all slots connected to the *contained\_value\_changed* signal.

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_child**(*name, widget, location=None, gui\_values\_path=True*)

Add a contained child widget.

*name* specifies the child storage name; if *name==False*, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location=="skip"*, skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when *clear* or *remove\_child* methods are called; otherwise, simply its *clear* method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is *False* or *None*, do not add it to the GUI values table; if it is *True*, add it under the same root (*path==""*) if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values**(*name, widget, path, add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path==""* or ends in *"/"* (e.g., *"subpath/"*), use its *setup\_gui\_values* to make it share the same GUI values; otherwise, simply add it to the GUI values under the



given path. if `add_change_event==True`, changing of the widget's value emits the container's `contained_value_changed` event

**add\_decoration\_label**(*text*, *location*='next', *tag*=None)

Add a decoration text label with the given text

**add\_padding**(*kind*='auto', *location*='next', *stretch*=0, *tag*=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_spacer**(*height*=0, *width*=0, *stretch\_height*=False, *stretch\_width*=False, *stretch*=0, *location*='next', *tag*=None)

Add a spacer with the given width and height to the given location.

If *stretch\_height*==True or *stretch\_width*==True, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind*=="both", it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_timer**(*name*, *period*, *autostart*=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling `start()` method), start the timer as well.

**add\_timer\_event**(*name*, *loop*=None, *start*=None, *stop*=None, *period*=None, *timer*=None, *autostart*=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling `start()` method), start the timer as well.

**add\_to\_layout**(*element*, *location*=None, *kind*='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**change\_layout\_tags**(*add*=None, *remove*=None, *replace*=None)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**contained\_value\_changed** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (sublayout, location), where sublayout is the sublayout name ("name" for the main layout), and location is a tuple (row, column, rowspan, colspan). If the given widget is not in this layout, return None.

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_layout\_shape**(*name=None*)

Get shape (rows, cols) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**insert\_column**(*col*, *sublayout=None*, *stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row*, *sublayout=None*, *stretch=0*)

Insert a new row at the given location in the grid layout

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**iter\_sublayout\_items**(*name=None*, *include=('widget',)*, *nested=False*, *tag=None*,  
*yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (kind, element), where kind can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (kind, element, layout, index), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element*, *location*)

Move the given layout element to a new location

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name=None*, *include='all'*, *nested=True*, *tag=None*, *widget\_action='remove'*)

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**set\_column\_stretch**(\*args, layout=None)

Set column stretch for a given layout.

Takes either two arguments **index** and **stretch**, or a single list of stretches for all columns.

**set\_row\_stretch**(\*args, layout=None)

Set row stretch for a given layout.

Takes either two arguments **index** and **stretch**, or a single list of stretches for all rows.

**setup\_name**(name)

Set the object's name

**start**()

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer**(name)

Start the timer with the given name (also called automatically on **start()** method)

**stop**()

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer**(name)

Stop the timer with the given name (also called automatically on **stop()** method)

**using\_layout**(name)

Use a different sublayout as default inside the **with** block

**using\_layout\_tags**(add=None, remove=None, replace=None)

Context manager for temporarily using different layout tags.

See **change\_layout\_tags()** for details.

**class** `pylablib.core.gui.widgets.param_table.StatusTable`(parent=None, name=None)

Bases: `ParamTable`

Expansion of `ParamTable` which adds status lines, which automatically subscribe to signals and update values.

**setup**(name=None, add\_indicator=True, gui\_thread\_safe=False, cache\_values=False, change\_focused\_control=False)

Setup the table.

#### Parameters

- **name** (*str*) – table widget name
- **add\_indicator** (*bool*) – if True, add indicators for all added widgets by default.
- **gui\_thread\_safe** (*bool*) – if True, all value-access and indicator-access calls (**get/set\_value**, **get/set\_all\_values**, **get/set\_indicator**, and **update\_indicators**) are automatically called in the GUI thread.
- **cache\_values** (*bool*) – if True or "update\_one", store a dictionary with all the current values and update it every time a GUI value is changed; provides a thread-safe way to check current parameters without lag (unlike **get\_value()** or **get\_all\_values()** with **gui\_thread\_safe==True**, which re-route calls to a GUI thread and may cause up to 100ms delay) can also be set to "update\_all", in which

case change of any value will cause value update of all variables; otherwise, change of a value will only cause update of that same value (might potentially miss some value updates for custom controls).

- **change\_focused\_control** (*bool*) – if False and `set_value()` method is called while the widget has user focus, ignore the value; note that `set_all_values()` will still set the widget value.

**add\_status\_line**(*name*, *label=None*, *srcs=None*, *tags=None*, *filt=None*, *fmt=None*)

Add a status line to the table:

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **label** (*str*) – if not None, specifies label to put in front of the status line
- **srcs** (*list*) – status signal sources
- **tags** (*list*) – status signal tags
- **filt** (*list*) – filter function for the signals
- **fmt** – if not None, specifies a function which takes 3 arguments (signal source, tag, and value) and generates a status line text.

**update\_status\_line**(*name*, *thread=None*, *path=None*)

Update status line to the variable with the given *path* from the thread with the given *thread* name.

If *thread* is None, use *srcs* name provided upon creation. If *path* is None, use *tags* name provided upon creation.

**TimerUIDGenerator** = <pylablib.core.utils.general.NamedUIDGenerator object>

**add\_button**(*name*, *caption*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a button to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str*) – text on the button
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_button\_selector**(*name*, *value=None*, *options=None*, *index\_values=None*, *out\_of\_range='reset'*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a combo box to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** – specifies initial value
- **options** (*list*) – list of strings specifying box options or a dictionary {option: index\_value}

- **index\_values** (*list*) – list of values corresponding to box options; if supplied, these values are used when setting/getting values or sending signals; if *options* is a dictionary, this parameter is ignored
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "reset" (reset to no-value position), or "ignore" (keep current value).
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_check\_box**(*name, caption, value=False, label=None, add\_indicator=None, location=None, tooltip=None, add\_change\_event=True, virtual=False*)

Add a checkbox to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str*) – text on the checkbox
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_child**(*name, widget, location=None, gui\_values\_path=True*)

Add a contained child widget.

*name* specifies the child storage name; if *name*==False, only add the widget to they layout, but not to the container. *location* specifies the layout location to which the widget is added; if *location*=="skip", skip adding it to the layout (can be manually added later). Note that if the widget is added to the layout, it will be completely deleted when `clear` or `remove_child` methods are called; otherwise, simply its `clear` method will be called, and its GUI values will be deleted.

If *gui\_values\_path* is False or None, do not add it to the GUI values table; if it is True, add it under the same root (*path*=="") if it's a container, and under *name* if it's not; otherwise, *gui\_values\_path* specifies the path under which the widget values are stored.

**add\_child\_values**(*name, widget, path, add\_change\_event=True*)

Add child's values to the container's table.

If *widget* is a container and *path*==" " or ends in "/\*" (e.g., "subpath/\*"), use its `setup_gui_values` to make it share the same GUI values; otherwise, simply add it to the GUI values under the given path. if *add\_change\_event*==True, changing of the widget's value emits the container's `contained_value_changed` event

**add\_combo\_box**(*name, value=None, options=None, index\_values=None, out\_of\_range='reset', label=None, add\_indicator=None, location=None, tooltip=None, add\_change\_event=True, virtual=False*)

Add a combo box to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** – specifies initial value
- **options** (*list*) – list of strings specifying box options or a dictionary {option: index\_value}

- **index\_values** (*list*) – list of values corresponding to box options; if supplied, these values are used when setting/getting values or sending signals; if *options* is a dictionary, this parameter is ignored
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "reset" (reset to no-value position), or "ignore" (keep current value).
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_custom\_widget**(*name, widget, value\_handler=None, indicator\_handler=None, location=None, tooltip=None, add\_change\_event=True*)

Add a 'custom' (multi-spaced, possibly complex-valued) widget to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **widget** – widget to add
- **value\_handler** – value handler of the widget; by default, use auto-detected value handler (works for many simple built-in or custom widgets)
- **indicator\_handler** – indicator handler of the widget; by default, use auto-detected indicator handler (use `set/get_indicator` methods if present, or no indicator otherwise)
- **location** (*tuple*) – tuple (row, column, rowspan, colspan) specifying location of the widget; by default, add to a new row in the end and into the first column, span one row and all table columns can also be a string "skip", which means that the widget is added to some other location manually later
- **add\_change\_event** (*bool*) – if True, changing of the widget's value emits the table's `contained_value_changed` event

Return the widget's value handler

**add\_decoration\_label**(*text, location='next', tag=None*)

Add a decoration text label with the given text

**add\_dropdown\_button**(*name, caption, options=None, index\_values=None, label=None, add\_indicator=None, location=None, tooltip=None, add\_change\_event=True, virtual=False*)

Add a button which shows a dropdown menu when clicked.

Similar in behavior to a regular button, but its changed event provides a single argument which is the name of the selected item.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str* or *list*) – text on the button
- **options** (*list*) – list of strings specifying menu options
- **index\_values** (*list*) – list of values corresponding to menu options; if supplied, these values are used when setting/getting values or sending signals.
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_enum\_label**(*name*, *options*, *value=None*, *out\_of\_range='error'*, *prep=None*, *styles=None*, *label=None*, *location=None*, *tooltip=None*, *add\_change\_event=False*, *virtual=False*)

Add a text label to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **options** (*dict*) – dictionary {*index\_value*: *text*} which converts values into text
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "text" (convert value into text), or "ignore" (keep current value).
- **prep** – a function which takes a single value argument and converts into an option; useful for “fuzzy” options (e.g., when 0 and False mean the same thing)
- **styles** – a dictionary {*value*: *style*} which defines stylesheet styles based on the value (if some values are not in the dictionary, use default no-style value)
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_frame**(*name*, *layout='vbox'*, *location=('next', 0, 1, 'end')*, *gui\_values\_path=True*, *no\_margins=True*)

Add a new frame container to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins==True*, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_group\_box**(*name*, *caption*, *layout='vbox'*, *location=('next', 0, 1, 'end')*, *gui\_values\_path=True*, *no\_margins=True*)

Add a new group box container with the given *caption* to the layout.

*layout* specifies the layout ("vbox", "hbox", or "grid") of the new frame, and *location* specifies its location within the container layout. If *no\_margins==True*, the frame will have no inner layout margins. The other parameters are the same as in [add\\_child\(\)](#) method.

**add\_num\_edit**(*name*, *value=None*, *limiter=None*, *formatter=None*, *custom\_steps=None*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a numerical edit to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **limiter** (*tuple*) – tuple (*upper\_limit*, *lower\_limit*, *action*, *value\_type*) specifying value limits; see [NumEdit.set\\_limiter\(\)](#) for details
- **formatter** (*tuple*) – either "int" (for integer values), or tuple specifying floating value format; see [NumEdit.set\\_formatter\(\)](#) for details
- **custom\_steps** – if not None, can specify custom fixed value steps when up/down keys are pressed with a modifier key (Control, Alt, or Shift) specifies a dictionary {'ctrl':ctrl\_step, 'alt':alt\_step, 'shift':shift\_step} with the corresponding steps (missing elements mean that the modifier key is ignored)

- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_num\_label**(*name*, *value*=0, *limiter*=None, *formatter*=None, *label*=None, *tooltip*=None, *location*=None, *add\_change\_event*=False, *virtual*=False)

Add a numerical label to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*float*) – specifies initial value
- **limiter** (*tuple*) – tuple (upper\_limit, lower\_limit, action, value\_type) specifying value limits; see `limiter.as_limiter()` for details
- **formatter** (*tuple*) – either "int" (for integer values), or tuple specifying floating value format; see `formatter.as_formatter()` for details
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_padding**(*kind*='auto', *location*='next', *stretch*=0, *tag*=None)

Add a padding (expandable spacer) of the given kind to the given location.

*kind* can be "vertical", "horizontal", "auto" (vertical for grid and vbox layouts, horizontal for hbox), or "both" (stretches in both directions). If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); can also be a tuple with two stretches along vertical and horizontal directions.

**add\_progress\_bar**(*name*, *value*=None, *label*=None, *location*=None, *tooltip*=None, *add\_change\_event*=True, *virtual*=False)

Add a progress bar to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as `add_simple_widget()`.

**add\_property\_element**(*name*, *getter*=None, *setter*=None, *add\_indicator*=True)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If *add\_indicator*==True, add default (stored value) indicator handler as well.

**add\_simple\_widget**(*name*, *widget*, *label*=None, *value\_handler*=None, *add\_indicator*=None, *location*=None, *tooltip*=None, *add\_change\_event*=True)

Add a 'simple' (single-spaced, single-valued) widget to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)



- **widget** – widget to add
- **label** (*str*) – if not None, specifies label to put in front of the widget in the layout
- **value\_handler** – value handler of the widget; by default, use auto-detected value handler (works for many simple built-in or custom widgets)
- **add\_indicator** – if True, add an indicator label in the third column and a corresponding indicator handler in the built-in values table; by default, use the default value supplied to *setup()*
- **location** (*tuple*) – tuple (row, column) specifying location of the widget (or widget label, if it is specified); by default, add to a new row in the end and into the first column can also be a string "skip", which means that the widget is added to some other location manually later (this option only works if *label=None*, and doesn't add any indicator)
- **tooltip** – widget tooltip (mouseover text)
- **add\_change\_event** (*bool*) – if True, changing of the widget's value emits the table's *contained\_value\_changed* event

Return the widget's value handler

**add\_spacer**(*height=0, width=0, stretch\_height=False, stretch\_width=False, stretch=0, location='next', tag=None*)

Add a spacer with the given width and height to the given location.

If *stretch\_height==True* or *stretch\_width==True*, the widget will stretch in these directions; otherwise, the widget size is fixed. If *stretch* is not None, it specifies stretch of the spacer the corresponding direction (applied to the upper row and leftmost column for multi-cell spacer); if *kind=="both"*, it can also be a tuple with two stretches along vertical and horizontal directions.

**add\_style\_indicator\_label**(*name, caption, options=(True, False), value=False, out\_of\_range='error', prep=<class 'bool'>, styles=None, label=None, location=None, tooltip=None, add\_change\_event=False, virtual=False*)

Add a label to the table with a fixed caption but whose style indicates the value.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** – text on the label
- **options** (*list*) – list with the possible values
- **out\_of\_range** (*str*) – behavior when out-of-range value is applied; can be "error" (raise error), "text" (convert value into text), or "ignore" (keep current value).
- **prep** – a function which takes a single value argument and converts into an option; useful for "fuzzy" options (e.g., when 0 and False mean the same thing)
- **styles** – a dictionary {value: style} which defines stylesheet styles based on the value (if some values are not in the dictionary, use default no-style value); can be a single string value, which gets assigned to True value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as *add\_simple\_widget()*.

**add\_sublayout**(*name*, *kind*='grid', *location*=('next', 0, 1, 'end'))

Add a sublayout to the given location.

*name* specifies the sublayout name, which can be used to refer to it in specifying locations later. *kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

**add\_text\_edit**(*name*, *value*="", *label*=None, *multiline*=False, *add\_indicator*=None, *location*=None, *tooltip*=None, *add\_change\_event*=True, *virtual*=False)

Add a text edit to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **multiline** (*bool*) – if True, use multi-line text edit widget; otherwise, use a standard single-line edit
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_text\_label**(*name*, *value*="", *label*=None, *location*=None, *tooltip*=None, *add\_change\_event*=False, *virtual*=False)

Add a text label to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if True, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_timer**(*name*, *period*, *autostart*=True)

Add a periodic timer with the given *name* and *period*.

Rarely needs to be called explicitly (one is created automatically if timer event is created). If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_timer\_event**(*name*, *loop*=None, *start*=None, *stop*=None, *period*=None, *timer*=None, *autostart*=True)

Add timer event with the given *name*.

Add an event which should be called periodically (e.g., a GUI update). Internally implemented through Qt timers. *loop*, *start* and *stop* are the functions called, correspondingly, on timer (periodically), when timer is start, and when it's finished. One can either specify the timer by name (*timer* parameter), or create a new one with the given *period*. If *autostart*==True and the container has been started (by calling [start\(\)](#) method), start the timer as well.

**add\_to\_layout**(*element*, *location*=None, *kind*='widget')

Add an existing *element* to the layout at the given *location*.

*kind* can be "widget" for widgets, "layout" for other layouts, or "item" for layout items (spacers).

**add\_toggle\_button**(*name*, *caption*, *value=False*, *label=None*, *add\_indicator=None*, *location=None*, *tooltip=None*, *add\_change\_event=True*, *virtual=False*)

Add a toggle button to the table.

#### Parameters

- **name** (*str*) – widget name (used to reference its value in the values table)
- **caption** (*str* or *list*) – text on the button; can be a single string, or a list of two strings which specifies the caption for off and on states
- **value** (*bool*) – specifies initial value
- **virtual** (*bool*) – if *True*, the widget is not added, and a virtual handler is added instead

Rest of the arguments and the return value are the same as [add\\_simple\\_widget\(\)](#).

**add\_virtual\_element**(*name*, *value=None*, *multivalued=False*, *on\_set\_value='store'*, *signal\_kind='none'*, *add\_indicator=None*)

Add a virtual table element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If *multivalued==True*, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. *on\_set\_value* specifies the behavior when value is set; can be "store" (store as the current value and return on *get\_value* later) or "ignore" (keep the original value) *signal\_kind* specifies value changed signal kind; can be "none" (no signal), "direct" (emulation of direct-connection signal, which is called whenever the value changes), or "dummy" (emulation of direct-connection signal, which is never called). If *add\_indicator==True*, add default indicator handler as well.

**change\_layout\_tags**(*add=None*, *remove=None*, *replace=None*)

Specify the current tags which are applied to every added layout elements.

*add*, *remove* specify, respectively, tags to be added, removed. *replace`* is specified, it completely replaces the set of current tags (before *add* and *remove* are applied).

**clear**(*disconnect=False*)

Clear the table (remove all widgets)

If *disconnect==True*, also disconnect all slots connected to the *contained\_value\_changed* signal.

```
contained_value_changed = <Mock name='mock.QtCore.pyqtSignal()'
id='140527858977616'>
```

**get\_all\_indicators**()

Get indicator values of all widget in the container

**get\_all\_values**()

Get values of all widget in the container

**get\_child**(*name*)

Get the child widget with the given name

**get\_element\_position**(*element*)

Get the sublayout and the position of the given widget.

Return tuple (*sublayout*, *location*), where *sublayout* is the sublayout name ("name" for the main layout), and *location* is a tuple (*row*, *column*, *rowspan*, *colspan*). If the given widget is not in this layout, return *None*.

**get\_handler**(*name*)

Get value handler of a widget with the given name

**get\_indicator**(*name=None*)

Get indicator value for a widget with the given name (None means all indicators)

**get\_indicator\_widget**(*name*)

Get indicator widget for a parameter with the given name, or None if this parameter has no indicator label

**get\_label\_widget**(*name*)

Get label widget for a parameter with the given name, or None if this parameter has no label

**get\_layout\_shape**(*name=None*)

Get shape (rows, cols) of the current layout

**get\_layout\_tags**()

Get the set of currently applied layout tags

**get\_sublayout**(*name=None*)

Get the previously added sublayout

**get\_sublayout\_kind**(*name=None*)

Get the kind of the previously added sublayout

**get\_value**(*name=None*)

Get value of a widget with the given name (None means all values)

**get\_value\_changed\_signal**(*name*)

Get a value-changed signal for a widget with the given name

**get\_widget**(*name*)

Get a widget corresponding to a value with the given name

**insert\_column**(*col, sublayout=None, stretch=0*)

Insert a new column at the given location in the grid layout

**insert\_row**(*row, sublayout=None, stretch=0*)

Insert a new row at the given location in the grid layout

**is\_running**()

Check if the container is running (started and not yet stopped)

**is\_stopping**()

Check if the container is stopping (stopping initialized and not yet done)

**is\_timer\_running**(*name*)

Check if the timer with the given name is running

**iter\_sublayout\_items**(*name=None, include=('widget',), nested=False, tag=None, yield\_layout\_info=False*)

Iterate over items contained in a given sublayout.

*include* is a tuple which contains items to iterate over; can include "widget", "layout", or "spacer". If *nested==True*, iterate over items in contained layouts and widgets as well. If *tag* is set, it specifies the tag to select the elements. If *yield\_layout\_info==False*, yield a 2-tuple (kind, element), where kind can be "widget", "layout", or "spacer"; if *yield\_layout\_info==True*, yield a 4-tuple (kind, element, layout, index), which includes the element's containing layout and its index within.

**move\_layout\_element**(*element*, *location*)

Move the given layout element to a new location

**pad\_borders**(*kind*='both', *stretch*=0)

Add expandable paddings on the bottom and/or right border.

*kind* can be "bottom", "right", "both", or "none" (do nothing). Note that if more elements are added, they will be placed after the padding, so the table will be padded in the middle.

**remove\_child**(*name*, *clear*=True)

Remove widget from the container and the layout and (if *clear*==True) clear it, and remove it

**remove\_layout\_element**(*element*)

Remove a previously added layout element

**remove\_sublayout\_items**(*name*=None, *include*='all', *nested*=True, *tag*=None, *widget\_action*='remove')

Remove items within the sublayout with the given name (current by default).

*include* specifies which elements to include (can be a tuple containing "widget", "layout", or "spacer", or "all"), *nested* specifies if nested layouts and widgets are also checked, *tag* specifies a possible tag to select the elements on. *widget\_action* can be "remove" (remove widgets and layouts), or "hide" (hide widgets without removing); spacers are always removed.

**remove\_widget**(*name*)

Remove the widget and, if applicable, its indicator and label

**set\_all\_indicators**(*value*, *ignore\_missing*=True)

**set\_all\_values**(*value*, *force*=True)

Set values of all widgets in the table.

If *force*==True, force widget value (e.g., ignoring restriction on not changing values of focused widgets)

**set\_column\_stretch**(\**args*, *layout*=None)

Set column stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all columns.

**set\_enabled**(*names*=None, *enabled*=True, *include\_indicator*=True, *include\_label*=True)

Enable or disable widgets with the given names (by default, all widgets)

**set\_indicator**(*name*, *value*, *ignore\_missing*=False)

Set indicator value for a widget or a branch with the given name

**set\_row\_stretch**(\**args*, *layout*=None)

Set row stretch for a given layout.

Takes either two arguments *index* and *stretch*, or a single list of stretches for all rows.

**set\_value**(*name*, *value*, *force*=True)

Set value of a widget with the given name.

If *force*==True, force widget value (e.g., ignoring restriction on not changing values of focused widgets)

**set\_visible**(*names*=None, *visible*=True, *include\_indicator*=True, *include\_label*=True)

Show or hide widgets with the given names (by default, all widgets)

**setup\_name**(*name*)

Set the object's name

**start()**

Start the container.

Starts all the internal timers, and calls **start** method for all the contained widgets.

**start\_timer(name)**

Start the timer with the given name (also called automatically on [start\(\)](#) method)

**stop()**

Stop the container.

Stops all the internal timers, and calls **stop** method for all the contained widgets.

**stop\_timer(name)**

Stop the timer with the given name (also called automatically on [stop\(\)](#) method)

**update\_indicators()**

Update all indicators to represent current values

**update\_value(name=None)**

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

**using\_layout(name)**

Use a different sublayout as default inside the **with** block

**using\_layout\_tags(add=None, remove=None, replace=None)**

Context manager for temporarily using different layout tags.

See [change\\_layout\\_tags\(\)](#) for details.

**using\_new\_sublayout(name, kind='grid', location=('next', 0, 1, 'end'))**

Create a different sublayout and use it as default inside the **with** block.

*kind* can be "grid", "vbox" (vertical single-column box), or "hbox" (horizontal single-row box).

## Module contents

### Submodules

#### pylablib.core.gui.formatter module

**pylablib.core.gui.formatter.parse\_float(s)**

Parse string as a float, with metric prefixes recognition.

Return tuple (sign, integer, dot, fractional, exponent, prefix), where each entry has structure (begin, end, text). Return *None* if string is unrecognizable.

**pylablib.core.gui.formatter.pos\_to\_order(s, pos)**

For a given string representation of a float and position in the string, get the decimal order for this position.

Return *None* if string is un-parsable or position is out of range (not in mantissa section of the number).

`pylablib.core.gui.formatter.order_to_pos(s, order)`

For a given string representation of float and decimal order, get the position in the string corresponding to this order.

If order is out of range for a given representation, truncates to most/least significant digit position. Return None if string is un-parsable.

`pylablib.core.gui.formatter.str_to_float(s)`

Return float value of a string, with metric prefixes recognition.

Raise `ValueError` if string is unrecognizable.

`pylablib.core.gui.formatter.is_integer(n, tolerance=0.0)`

Check if *n* is less than *tolerance* away from the nearest integer.

`pylablib.core.gui.formatter.float_to_str_SI(n, digits=3, trailing_zeros=False)`

Represent float using SI metric prefixes.

For orders  $\geq 27$  and  $\leq -24$  use usual scientific notation with order being multiple of 3. If `trailing_zeros==True`, then digits define precision, rather than number significant digits

```
class pylablib.core.gui.formatter.FloatFormatter(output_format='auto', digits=3,
                                                add_trailing_zeros=True, leading_zeros=0,
                                                explicit_sign=False)
```

Bases: `object`

Floating point number formatter.

Callable object with takes a number as an argument and returns is string representation.

#### Parameters

- **output\_format** (*str*) – can be "auto" (use standard Python conversion), "SI" (use SI prefixes if possible), or "sci" (scientific "E" notation).
- **digits** (*int*) – if `add_trailing_zeros==False`, determines the number of significant digits; otherwise, determines precision (number of digits after decimal point).
- **add\_trailing\_zeros** (*bool*) – if `True`, always show fixed number of digits after the decimal point, with zero padding if necessary.
- **leading\_zeros** (*bool*) – determines the minimal size of the integer part (before the decimal point) of the number; pads with zeros if necessary.
- **explicit\_sign** (*bool*) – if `True`, always add explicit plus sign.

```
class pylablib.core.gui.formatter.IntegerFormatter
```

Bases: `object`

Simple integer number formatter.

Callable object with takes a number as an argument and returns is string representation.

For more flexibility (e.g., adding leading zeros) it is possible to use `FloatFormatter` with `digits=0` and `add_trailing_zeros=True`.

```
class pylablib.core.gui.formatter.FmtStringFormatter(fmt)
```

Bases: `object`

Formatter based on format string.

Callable object with takes a number as an argument and returns is string representation.

`pylablib.core.gui.formatter.as_formatter(formatter)`

Turn an object into a formatter.

Can be a callable object turning value into a string, a string ("float", "int", or a format string, e.g., ".5f"), or a tuple starting with "float" which contains arguments to the [FloatFormatter](#).

## pylablib.core.gui.limiter module

**exception** `pylablib.core.gui.limiter.LimitError(value, lower_limit=None, upper_limit=None)`

Bases: [ArithmeticError](#)

Error raised when the value is out of limits and can't be coerced

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.core.gui.limiter.NumberLimit(lower_limit=None, upper_limit=None, action='coerce', value_type=None)`

Bases: [object](#)

Number limiter, which checks validity of user inputs.

Callable object with takes a number as an argument and either returns its coerced version (or the number itself, if it is within limits), or raises [LimitError](#) if it should be ignored.

### Parameters

- **lower\_limit** – lower limit (inclusive), or None if there is no limit.
- **upper\_limit** – upper limit (inclusive), or None if there is no limit.
- **action** (*str*) – action taken if the number is out of limits; either "coerce" (return the closest valid value), or "ignore" (raise [LimitError](#)).
- **value\_type** (*str*) – determines value type coercion; can be None (do nothing, only check limits), "float" (cast to float), or "int" (cast to integer).

**cast(value)**

`pylablib.core.gui.limiter.filter_limiter(pred)`

Turn a predicate into a limiter.

Returns a function that raises [LimitError](#) if the predicate is false.

`pylablib.core.gui.limiter.as_limiter(limiter)`

Turn an object into a limiter.

Limiter can be a callable object which takes a single value and either returns a limited value, or raises [LimitError](#) if it should be ignored; or it can be a tuple (lower, upper, action, value\_type), where lower and upper are the limits (None means no limits), action defines out-of-limit action (either "ignore" to ignore entered value, or "coerce" to truncate to the nearest limit), and value\_type can be None (keep value as is), "float" (cast value to float), "int" (cast value to int). If the tuple is shorter, the missing parts are filled by default values (None, None, "ignore", None).



**pylablib.core.gui.utils module**

`pylablib.core.gui.utils.get_top_parent(widget)`

Find the top-level parent (parent which does not have further parents)

`pylablib.core.gui.utils.find_layout_element(layout, element)`

Find a layout element.

Can be a widget, a sublayout, or a layout element Return item index within the layout. If layout is empty or item is not present, return `None`

`pylablib.core.gui.utils.delete_layout_item(layout, idx)`

Remove an item with the given index (completely delete it)

`pylablib.core.gui.utils.clean_layout(layout, delete_layout=False)`

Delete all items from the layout.

If `delete_layout==True`, delete the layout as well.

`pylablib.core.gui.utils.get_layout_container(widget, top=None, kind='widget')`

Find a container widget or layout which contains the given widget.

Note that the container widget does not necessarily correspond to the element parent. If no container could be found, return `None`. If *kind* can be either "widget" (return the containing widget), or "layout" (return the containing layout, which is a layout or sublayout of the containing widget).

This method works by traversing the whole layout tree, so it can be relatively slow. *top* can specify the top container (widget or layout) which definitely contains the given widget; if not specified, use the top-level parent found by `get_top_parent()`.

`pylablib.core.gui.utils.get_all_layout_containers(widget, top=None, kind='widget')`

Get a list of all widgets or layouts containing the current widget.

The list is arranged from the bottom of the hierarchy (starting from *widget*) to the *top*. Note that the container widget does not necessarily correspond to the element parent. If no containers could be found, return `None`. If *kind* can be either "widget" (return the containing widgets), or "layout" (return the containing layouts, which are layouts or sublayouts of the containing widgets).

This method works by traversing the whole layout tree, so it can be relatively slow. *top* can specify the top container (widget or layout) which definitely contains the given widget; if not specified, use the top-level parent found by `get_top_parent()`.

`pylablib.core.gui.utils.delete_widget(widget)`

Remove widget from its layout container and delete it

`class pylablib.core.gui.utils.TWidgetLocation(layout, position)`

Bases: `tuple`

**layout**

**position**

`pylablib.core.gui.utils.get_widget_location(widget, layout=None)`

Get location of a widget within the given layout.

Return tuple (*layout*, *position*), where *layout* is the layout object, and *position* is either a single position number (for box layouts), or a tuple (*row*, *col*, *rowspan*, *colspan*) for a grid layout. If layout is not specified, autodetect it.

`pylablib.core.gui.utils.place_widget_at_location(widget, location)`

Insert a widget within the given layout location.

*location* is a tuple tuple (layout, position), where *layout* is the layout object, and *position* is either a single position number (for box layouts), or a tuple (row, col, rowspan, colspan) for a grid layout. The tuple has the same format as returned by `get_widget_location()`.

`pylablib.core.gui.utils.is_layout_row_empty(layout, row)`

Check if the given row in a grid layout is empty

`pylablib.core.gui.utils.get_last_filled_row(layout, start_row=0)`

Find the last non-empty row in a grid layout after *start\_row* (inclusive).

If all rows after (and including) *start\_row* are empty, return `None`.

`pylablib.core.gui.utils.get_first_empty_row(layout, start_row=0)`

Find the first completely empty row in a grid layout after *start\_row* (inclusive)

`pylablib.core.gui.utils.insert_layout_row(layout, row, stretch=0, compress=False)`

Insert row in a grid layout at a given index.

Any multi-column item spanning over the row (i.e., starting at least one row before *row* and ending at least one row after *row*) gets stretched. Anything else either stays in place (if it's above *row*), or gets moved one row down. *stretch* determines the stretch factor of the new row. If `compress==True`, try to find an empty row below the inserted position and shift it to the new row's place; otherwise, add a completely new row.

`pylablib.core.gui.utils.is_layout_column_empty(layout, col)`

Check if the given column in a grid layout is empty

`pylablib.core.gui.utils.get_last_filled_column(layout, start_col=0)`

Find the last non-empty column in a grid layout after *start\_col* (inclusive).

If all rows after (and including) *start\_col* are empty, return `None`.

`pylablib.core.gui.utils.get_first_empty_column(layout, start_col=0)`

Find the first completely empty column in a grid layout after *start\_col* (inclusive)

`pylablib.core.gui.utils.insert_layout_column(layout, col, stretch=0, compress=False)`

Insert column in a grid layout at a given index.

Any multi-row item spanning over the column (i.e., starting at least one column before *col* and ending at least one column after *col*) gets stretched. Anything else either stays in place (if it's above *col*), or gets moved one column to the right. *stretch* determines the stretch factor of the new column. If `compress==True`, try to find an empty column below the inserted position and shift it to the new column's place; otherwise, add a completely new column.

`pylablib.core.gui.utils.compress_grid_layout(layout)`

Find all empty rows in a grid layout and shift them to the bottom

`pylablib.core.gui.utils.get_relative_position(widget, origin=None)`

Get widget's position relative to the origin (top-level parent if `None`)

`pylablib.core.gui.utils.get_relative_rectangle(widget, origin=None, border=0, trim_border=True)`

Get widget rectangle area relative to the origin (top-level parent if `None`).

If *border* is non-zero, it specifies a border (integer or 2-tuple) around the widget to add to the rectangle. If `trim_border==True`, the resulting rectangle is trimmed to lie within the origin area. Return `QRect` object.

`pylablib.core.gui.utils.get_screenshot(window=None, rect=None, widget=None, border=0, include_titlebar=True)`

Take a screenshot of a given window or a given widget.

Either *window* or *widget* must be defined. If *rect* (type `QRect`) or *widget* are defined, they specify the area to include into screenshot; in this case, *border* can define an additional border to add to the rectangle. If rectangle is not defined, then *include\_titlebar* specifies whether the window titlebar is included.

## pylablib.core.gui.value\_handling module

Uniform representation of values from different widgets: numerical and text edits and labels, combo and check boxes, buttons.

`pylablib.core.gui.value_handling.build_children_tree(root, types_include, is_atomic=None, is_excluded=None, self_node='#')`

`pylablib.core.gui.value_handling.has_methods(widget, methods_sets)`

Check if the widget has methods from given set.

*methods\_sets* is a list of method sets. The function returns `True` if the widget has at least one method from each of the sets.

`pylablib.core.gui.value_handling.get_method_kind(method, add_args=0)`

Determine whether the method takes name as its argument

*add\_args* specifies number of additional required arguments. Return "named" if the method has at least *add\_args*+1 arguments, and the first one is called "name". Otherwise, return "simple".

**exception** `pylablib.core.gui.value_handling.NoParameterError`

Bases: `KeyError`

Error raised by some handlers to indicate that the parameter is missing

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.core.gui.value_handling.IValueHandler(widget)`

Bases: `object`

Generic handler of a widget value.

Has method to get and set the value (or all values, if the widget has internal value structure), representing values as strings, and value changed signal.

**Parameters**

**widget** – handled widget.

**get\_value(name=None)**

Get widget value.

If *name* is not `None`, it specifies the name of the value parameter inside the widget (for complex widgets).



**Parameters**

- **value** – initial value
- **multivalued** (*bool*) – if True, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set.
- **on\_set\_value** – behavior when value is set; can be "store" (store as the current value and return on `get_value` later) or "ignore" (keep the original value)
- **signal\_kind** – value changed signal kind; can be "none" (no signal), "direct" (emulation of direct-connection signal, which is called whenever the value changes), or "dummy" (emulation of direct-connection signal, which is never called)

**get\_value\_changed\_signal()**

Get the Qt signal emitted when the value is changed

**get\_value**(*name=None*)

Get widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**set\_value**(*value, name=None*)

Set widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

**Parameters**

- **focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler, only\_signal=True*)

Connect value changed signal.

If *only\_signal*==True, equivalent to connecting a handler function to `get_value_changed_signal()` signal; however, if *only\_signal*==False, it also works for some objects (e.g., `QLabel`) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use `get_value_changed_signal()` directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their `disconnect` method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name*==None)

**repr\_value**(*value, name=None*)

Return textual representation of the value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

```
class pylablib.core.gui.value_handling.PropertyValueHandler(getter=None, setter=None,  
                                                         default_name=None)
```

Bases: [\*IValueHandler\*](#)

Virtual value handler which uses custom getter/setter methods to simulate a value.

If getter or setter are not supplied but are called, they raise [\*NoParameterError\*](#); this means that they are ignored in [\*GUIValues.get\\_all\\_values\(\)\*](#) and [\*GUIValues.set\\_all\\_values\(\)\*](#) methods, but raise an error when access directly (e.g., using [\*GUIValues.get\\_value\(\)\*](#)).

#### Parameters

- **getter** – value getter method; takes 0 or 1 (name) arguments and returns the value
- **setter** – value setter method; takes 1 (value) or 2 (name and value) arguments and sets the value
- **default\_name** (*str*) – default name to be supplied to **getter** and **setter** methods if they require a name argument

```
get_value(name=None)
```

Get widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

```
set_value(value, name=None)
```

Set widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

```
can_set_value(allow_focus=True)
```

Check if setting value from the code is allowed.

#### Parameters

- **focus** – if *False*, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

```
connect_value_changed_handler(handler, only_signal=True)
```

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., *QLabel*) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

```
disconnect_value_changed_handler(handler=None)
```

Disconnect value changed signal.

Works both for Qt signals (by calling their **disconnect** method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

```
get_handler(name=None)
```

Get handler of a contained widget (or same widget, if *name==None*)

```
get_value_changed_signal()
```

Get the Qt signal emitted when the value is changed

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**class** `pylablib.core.gui.value_handling.StandardValueHandler`(*widget*, *default\_name=None*)

Bases: [\*IValueHandler\*](#)

Standard value handler, typically used for custom widgets.

To implement getting and setting values, looks for `get/set_value` and `get/set_all_values` methods for the widget and uses them accordingly. To implement value representing, looks for `repr_value` method (if not defined, use simple string conversion). To implement value change signal, looks for `value_changed` widget signal.

#### Parameters

- **widget** – handled widget
- **default\_name** (*str*) – default name to be supplied to `get/set_value` and `get/set_all_values` methods if they require a name argument.

**get\_value**(*name=None*)

Get widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**set\_value**(*value*, *name=None*)

Set widget value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If *name* is not *None*, it specifies the name of the value parameter inside the widget (for complex widgets).

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

- **focus** – if *False*, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [`get\_value\_changed\_signal\(\)`](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., `QLabel`) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [`get\_value\_changed\_signal\(\)`](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their `disconnect` method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

**get\_value\_changed\_signal()**

Get the Qt signal emitted when the value is changed

**class** pylablib.core.gui.value\_handling.ISingleValueHandler(*widget*)

Bases: *IValueHandler*

Base class for single-value widget handler, typically used for built-in Qt widgets.

Defines new functions `get/set_single_value` which don't take a name argument; raises an error if the name is supplied to any of the standard functions.

**Parameters**

**widget** – handled widget

**get\_single\_value()**

Get the widget value

**get\_value**(*name=None*)

Get widget value.

If *name* is not `None` raise an error.

**set\_single\_value**(*value*)

Set the widget value

**set\_value**(*value, name=None*)

Set widget value.

If *name* is not `None` raise an error.

**repr\_single\_value**(*value*)

Represent the widget value as a string

**repr\_value**(*value, name=None*)

Return textual representation of the value.

If *name* is not `None` raise an error.

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

**Parameters**

**focus** – if `False`, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler, only\_signal=True*)

Connect value changed signal.

If *only\_signal*==`True`, equivalent to connecting a handler function to `get_value_changed_signal()` signal; however, if *only\_signal*==`False`, it also works for some objects (e.g., `QLabel`) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use `get_value_changed_signal()` directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their `disconnect` method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is `None`, disconnect all events.



**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**class** pylablib.core.gui.value\_handling.**LineEditValueHandler**(*widget*)

Bases: *ISingleValueHandler*

Value handler for QLineEdit widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if *False*, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler, only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to *get\_value\_changed\_signal()* signal; however, if *only\_signal==False*, it also works for some objects (e.g., QLabel) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use *get\_value\_changed\_signal()* directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their *disconnect* method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If *name* is not *None* raise an error.

**repr\_single\_value**(*value*)

Represent the widget value as a string

**repr\_value**(*value, name=None*)

Return textual representation of the value.

If *name* is not *None* raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If name is not None raise an error.

**class** pylablib.core.gui.value\_handling.LabelValueHandler(*widget*)

Bases: [\*ISingleValueHandler\*](#)

Value handler for QLabel widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., QLabel) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their *disconnect* method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is None, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If name is not None raise an error.

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_single\_value**(*value*)

Represent the widget value as a string

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If name is not None raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If *name* is not *None* raise an error.

**class** `pylablib.core.gui.value_handling.IBoolValueHandler`(*widget*, *labels=('Off', 'On')*)

Bases: [\*ISingleValueHandler\*](#)

Generic value handler for widgets with boolean values

**repr\_single\_value**(*value*)

Represent the widget value as a string

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if *False*, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., *QLabel*) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their *disconnect* method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_single\_value**()

Get the widget value

**get\_value**(*name=None*)

Get widget value.

If *name* is not *None* raise an error.

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If *name* is not *None* raise an error.

**set\_single\_value**(*value*)

Set the widget value

**set\_value**(*value*, *name*=None)

Set widget value.

If name is not None raise an error.

**class** pylablib.core.gui.value\_handling.**CheckboxValueHandler**(*widget*, *labels*=('Off', 'On'))

Bases: [\*IBoolValueHandler\*](#)

Value handler for QCheckBox widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**repr\_single\_value**(*value*)

Represent the widget value as a string

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**can\_set\_value**(*allow\_focus*=True)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal*=True)

Connect value changed signal.

If *only\_signal*==True, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal*==False, it also works for some objects (e.g., QLabel) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler*=None)

Disconnect value changed signal.

Works both for Qt signals (by calling their disconnect method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is None, disconnect all events.

**get\_handler**(*name*=None)

Get handler of a contained widget (or same widget, if *name*==None)

**get\_value**(*name*=None)

Get widget value.

If name is not None raise an error.

**repr\_value**(*value*, *name*=None)

Return textual representation of the value.

If name is not None raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If name is not None raise an error.

**class** `pylablib.core.gui.value_handling.PushButtonValueHandler`(*widget*, *labels=('Off', 'On')*)

Bases: [`IBoolValueHandler`](#)

Value handler for QPushButton widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_single\_value**(*value*)

Represent the widget value as a string

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [`get\_value\_changed\_signal\(\)`](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., `QLabel`) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [`get\_value\_changed\_signal\(\)`](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their `disconnect` method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is None, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If name is not None raise an error.

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If name is not None raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If name is not None raise an error.

**class** pylablib.core.gui.value\_handling.ToolButtonValueHandler(*widget*, *labels=('Off', 'On')*)

Bases: [\*IBoolValueHandler\*](#)

Value handler for QToolButton widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_single\_value**(*value*)

Represent the widget value as a string

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., *QLabel*) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their *disconnect* method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is *None*, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If name is not None raise an error.

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If name is not None raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If name is not None raise an error.

**class** pylablib.core.gui.value\_handling.ComboBoxValueHandler(*widget*)

Bases: [\*ISingleValueHandler\*](#)

Value handler for QComboBox widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_single\_value**(*value*)

Represent the widget value as a string

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., QLabel) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their disconnect method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is None, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If name is not None raise an error.

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If name is not None raise an error.

**set\_value**(*value*, *name=None*)

Set widget value.

If name is not None raise an error.

**class** pylablib.core.gui.value\_handling.ProgressBarValueHandler(*widget*)

Bases: [\*ISingleValueHandler\*](#)

Value handler for QProgressBar widget

**get\_single\_value**()

Get the widget value

**set\_single\_value**(*value*)

Set the widget value

**can\_set\_value**(*allow\_focus=True*)

Check if setting value from the code is allowed.

#### Parameters

**focus** – if False, indicates that settings of focused widgets isn't allowed, with some exceptions (buttons, check boxes, combo boxes)

**connect\_value\_changed\_handler**(*handler*, *only\_signal=True*)

Connect value changed signal.

If *only\_signal==True*, equivalent to connecting a handler function to [\*get\\_value\\_changed\\_signal\(\)\*](#) signal; however, if *only\_signal==False*, it also works for some objects (e.g., QLabel) don't have built-in on-changed signals by calling the handler explicitly every time the value is changed.

Note that the connection is always direct (i.e., it doesn't deal with message queues and different threads, but rather directly calls the handler function). If you need to connect a handler to a signal using some other connection method, you can use [\*get\\_value\\_changed\\_signal\(\)\*](#) directly.

**disconnect\_value\_changed\_handler**(*handler=None*)

Disconnect value changed signal.

Works both for Qt signals (by calling their disconnect method directly), and for emulated signals (used for non-signal-emitting widgets). If *handler* is None, disconnect all events.

**get\_handler**(*name=None*)

Get handler of a contained widget (or same widget, if *name==None*)

**get\_value**(*name=None*)

Get widget value.

If name is not None raise an error.

**get\_value\_changed\_signal**()

Get the Qt signal emitted when the value is changed

**repr\_single\_value**(*value*)

Represent the widget value as a string

**repr\_value**(*value*, *name=None*)

Return textual representation of the value.

If name is not None raise an error.



**set\_value**(*value*, *name=None*)

Set widget value.

If *name* is not *None* raise an error.

`pylablib.core.gui.value_handling.is_handled_widget(widget)`

Check if the widget can be handles by [StandardValueHandler](#)

`pylablib.core.gui.value_handling.create_value_handler(widget)`

Autodetect value handler for the given widget

**class** `pylablib.core.gui.value_handling.IIndicatorHandler`

Bases: `object`

Generic handler of an indicator.

Has methods to get and set the indicator value.

**get\_value**(*name=None*)

Get indicator value.

If *name* is not *None*, it specifies the name of the indicator parameter inside the widget (for complex widgets).

**set\_value**(*value*, *name=None*)

Set indicator value.

If *name* is not *None*, it specifies the name of the indicator parameter inside the widget (for complex widgets).

`pylablib.core.gui.value_handling.VirtualIndicatorHandler`

alias of [VirtualValueHandler](#)

**class** `pylablib.core.gui.value_handling.StandardIndicatorHandler(widget, default_name=None)`

Bases: [IIndicatorHandler](#)

Default indicator handler, typically used for custom widgets.

To implement getting and setting values, looks for `get/set_indicator` and `get/set_all_indicators` methods for the widget and uses them accordingly.

#### Parameters

- **widget** – handled widget
- **default\_name** (*str*) – default name to be supplied to `get/set_indicator` methods if they require a name argument.

**get\_value**(*name=None*)

Get indicator value.

If *name* is not *None*, it specifies the name of the indicator parameter inside the widget (for complex widgets).

**set\_value**(*value*, *name=None*)

Set indicator value.

If *name* is not *None*, it specifies the name of the indicator parameter inside the widget (for complex widgets).

```
class pylablib.core.gui.value_handling.LabelIndicatorHandler(label, formatter=None,  
                                                           repr_value_name=None)
```

Bases: [\*IIndicatorHandler\*](#)

Indicator handler which uses a label to show the value.

Can takes optional widget or widget handler which converts values into strings using its `repr_value` method (by default, use the standard string conversion).

#### Parameters

- **label** – widget or value handler used to represent the value (takes string values)
- **formatter** – specifies a way to turn values into string representation; can be a widget handler or a widget (its `repr_func` method is used to represent its value), a function (it takes either a single value argument or two arguments `name` and `value` and returns string value), or `None` (use simple string conversion)
- **repr\_value\_name** (*str*) – default name to be supplied to `repr_value` if it requires a name argument and name is not supplied

```
get_value(name=None)
```

Get indicator value.

If `name` is not `None`, it specifies the name of the indicator parameter inside the widget (for complex widgets).

```
repr_value(value, name=None)
```

Represent a value with a given name

```
set_value(value, name=None)
```

Set indicator value.

If `name` is not `None`, it specifies the name of the indicator parameter inside the widget (for complex widgets).

```
pylablib.core.gui.value_handling.create_indicator_handler(widget, label=None,  
                                                         require_setter=False)
```

Autodetect indicator handler for the given widget and optional indicator label

```
exception pylablib.core.gui.value_handling.MissingGUIHandlerError
```

Bases: [\*KeyError\*](#)

Missing GUI handler

```
add_note()
```

Exception.add\_note(note) – add a note to the exception

**args**

```
with_traceback()
```

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

```
class pylablib.core.gui.value_handling.GUIValues(gui_thread_safe=True)
```

Bases: [\*object\*](#)

A collection of values which can be used to manipulate many value handlers at once and represent them as a hierarchical structure.

Has four container-like accessor: `.h` for getting/adding/removing the value handler (i.e., `self.get_handler(name)` is equivalent to `self.h[name]`, and `self.add_handler(name, handler)` is equivalent to `self.h[name]=handler`, and `self.remove_handler(name)` is equivalent to `del self.h[name]`),

.w for getting the underlying widget (i.e., `self.get_widget(name)` is equivalent to `self.w[name]`), .v for settings/getting values (i.e., `self.get_value(name)` is equivalent to `self.v[name]`, and `self.set_value(name, value)` is equivalent to `self.v[name]=value`), .i for settings/getting indicator values (i.e., `self.get_indicator(name)` is equivalent to `self.i[name]`, and `self.set_indicator(name, value)` is equivalent to `self.i[name]=value`) .vs for getting the value changed Qt signal (i.e., `self.get_value_changed_signal(name)` is equivalent to `self.s[name]`),

#### Parameters

**gui\_thread\_safe** (*bool*) – if True, all value-access and indicator-access calls (`get/set_value`, `get/set_all_values`, `get/set_indicator`, `get/set_all_indicators`, and `update_indicators`) are automatically called in the GUI thread.

**add\_handler**(*name, handler*)

Add a value handler under a given name

**remove\_handler**(*name, remove\_indicator=True, disconnect=False*)

Remove the value handler with a given name.

If `remove_indicator==True`, also try to remove the indicator widget. If `disconnect==True`, also disconnect all slots connected to the `value_changed` signal. Unlike most methods (e.g., `get_value()` or `get_handler()`), does not recursively query the children, so it only works if the handler is contained in this table.

**get\_handler**(*name*)

Get the value handler with the given name

**add\_widget**(*name, widget, add\_indicator=True*)

Add a widget under a given name (value handler type is auto-detected)

**get\_widget**(*name*)

Get the widget corresponding to the handler under the given name

**add\_nested**(*name, gui\_values, add\_indicator=True*)

Add a nested *GUIValues* under a given name

**add\_virtual\_element**(*name, value=None, multivalued=False, on\_set\_value='store', signal\_kind='none', add\_indicator=True*)

Add a virtual value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view (its value can be set or read, it has on-change events, it can have indicator). The element value is simply stored on set and retrieved on get. If `multivalued==True`, the internal value is assumed to be complex, so it is forced to be a *Dictionary* every time it is set. `on_set_value` specifies the behavior when value is set; can be "store" (store as the current value and return on `get_value` later) or "ignore" (keep the original value) `signal_kind` specifies value changed signal kind; can be "none" (no signal), "direct" (emulation of direct-connection signal, which is called whenever the value changes), or "dummy" (emulation of direct-connection signal, which is never called). If `add_indicator==True`, add default indicator handler as well.

**add\_property\_element**(*name, getter=None, setter=None, add\_indicator=True*)

Add a property value element.

Doesn't correspond to any actual widget, but behaves very similarly from the application point of view; each time the value is set or get, the corresponding setter and getter methods are called. If `add_indicator==True`, add default (stored value) indicator handler as well.

**add\_all\_children**(*root*, *root\_name*=None, *types\_include*=None, *types\_exclude*=(), *names\_exclude*=None)

Add a widget and all its children to the values set.

The result is organized as a tree using parent-child relations (note that it implies that only children widgets correspond to tree nodes, i.e., only their values can be get/set).

#### Parameters

- **root** – root widget
- **root\_name** – path to the sub-branch where the values will be placed
- **types\_include** – if not None, specifies list of widget classes (e.g., QCheckBox) to include
- **types\_exclude** – specifies list of widget classes to exclude
- **names\_exclude** – if not None, specifies list of widget names to exclude

**class IndicatorsSet**(*ind*)

Bases: `tuple`

**ind**

**add\_indicator\_handler**(*name*, *handler*, *ind\_name*='\_\_default\_\_')

Add indicator handler with a given name.

*ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators.

**remove\_indicator\_handler**(*name*, *ind\_name*=None)

Remove indicator handler with a given name.

*ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators. By default, remove all indicators with this name

**add\_widget\_indicator**(*name*, *widget*, *label*=None, *ind\_name*='\_\_default\_\_')

Add widget-based indicator with a given name.

If *label* is None, use widget's `get/set_indicator` or `get/set_all_indicators` functions to indicate the value. Otherwise, use the given *label* to indicate the value (*label* is used to show the value, *widget* is used to represent it). *ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators.

**add\_label\_indicator**(*name*, *label*, *formatter*=None, *ind\_name*='\_\_default\_\_')

Add label-based indicator with a given name.

*formatter* specifies a way to turn values into string representation; can be a widget handler or a widget (its `repr_func` method is used to represent its value), a function (it takes either a single value argument or two arguments *name* and *value* and returns string value), or None (use simple string conversion) *ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators.

**get\_value**(*name*=None)

Get a value or a set of values in a subtree under a given name (all values by default).

Automatically handles complex widgets and sub-names. If *name* refers to a branch, return a [Dictionary](#) object containing tree structure of the names. If supplied, *include* and *exclude* are containers specifying included and excluded names (relative to the root); by default, include everything and exclude nothing.

**get\_all\_values**(*root=None*)

Get all values in the given sub-branch.

Same as [get\\_value\(\)](#), but returns an empty dictionary if the *name* is missing.

**set\_value**(*name, value*)

Set value under a given name.

Automatically handles complex widgets and sub-names

**set\_all\_values**(*value, root=None*)

**get\_indicator**(*name=None, ind\_name='\_\_default\_\_'*)

Get indicator value with a given name.

*ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators. If supplied, *include* and *exclude* are containers specifying included and excluded names (relative to the root); by default, include everything and exclude nothing.

**get\_all\_indicators**(*root=None, ind\_name='\_\_default\_\_'*)

Get all indicator values in the given sub-branch.

Same as [get\\_indicator\(\)](#), but returns an empty dictionary if the *root* is missing.

**set\_indicator**(*name, value, ind\_name=None, ignore\_missing=False*)

Set indicator value with a given name.

*ind\_name* can distinguish different sub-indicators with the same name, if the same value has multiple indicators. By default, set all sub-indicators to the given value. If supplied, *include* and *exclude* are containers specifying included and excluded names (relative to the root); by default, include everything and exclude nothing. If *ignore\_missing==True* and the given indicator and sub-indicator names are missing, raise an error; otherwise, do nothing.

**set\_all\_indicators**(*value, root="", ind\_name=None, ignore\_missing=True*)

**update\_indicators**(*root=""*)

Update all indicators in a subtree with the given root (all values by default) to represent current values.

If supplied, *include* and *exclude* are containers specifying included and excluded names (relative to the root); by default, include everything and exclude nothing.

**repr\_value**(*name, value*)

Get a textual representation of a value under a given name.

Automatically handles complex widgets and sub-names.

**get\_value\_changed\_signal**(*name*)

Get changed events for a value under a given name

**update\_value**(*name=None*)

Send update signal for a handler with a given name or list of names.

Emit a value changed signal with the current value to notify the subscribed slots. If *name* is *None*, emit for all values in the table.

`pylablib.core.gui.value_handling.get_gui_values(gui_values=None, gui_values_path="")`

Get new or existing [GUIValues](#) object and the sub-branch path inside it based on the supplied arguments.

If *gui\_values* is *None* or "new", create a new object and set empty root path. If *gui\_values* itself has *gui\_values* attribute, get this attribute, and prepend object's *gui\_values\_path* attribute to the given path. Otherwise, assume that *gui\_values* is [GUIValues](#) object, and use the supplied root.

`pylablib.core.gui.value_handling.virtual_gui_values(**kwargs)`

Create a gui values set with all virtual values.

kwargs define element names and default values.

## Module contents

### pylablib.core.thread package

#### Submodules

#### pylablib.core.thread.callsync module

`class pylablib.core.thread.callsync.QCallResultSynchronizer(skipable=True)`

Bases: [`QThreadNotifier`](#)

**get\_progress()**

Get the progress of the call execution.

Can be "waiting" (call is not done executing), "done" (call done successfully), "fail" (call failed, probably due to thread being stopped), "skip" (call was skipped), or "exception" (call raised an exception).

**is\_call\_done()**

Check if the call is done

**skipped()**

Check if the call was skipped

**failed()**

Check if the call failed

**get\_value\_sync**(*timeout=None, default=None, error\_on\_fail=True, error\_on\_skip=True, pass\_exception=True*)

Wait (with the given *timeout*) for the value passed by the notifier

If *error\_on\_fail==True* and the controlled thread notifies of a fail (usually, if it's stopped before it executed the call), raise [`threadprop.NoControllerThreadError`](#); otherwise, return *default*. If *error\_on\_skip==True* and the call was skipped (e.g., due to full call queue), raise [`threadprop.SkippedCallError`](#); otherwise, return *default*. If *pass\_exception==True* and the returned value represents exception, re-raise it in the caller thread; otherwise, return *default*.

**done\_notify()**

Check if notifying is done

**done\_wait()**

Check if waiting is done

**get\_value()**

Get the value passed by the notifier (doesn't check if it has been passed already)

**notify**(\*args, \*\*kwargs)

Notify the waiting process.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called before [`wait\(\)`](#), return immediately.

**notifying\_state()**

**success\_wait()**

Check if waiting is done successfully

**wait(\*args, \*\*kwargs)**

Wait for the notification.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called after [notify\(\)](#), return immediately.

**waiting()**

Check if waiting is in progress

**waiting\_state()**

**class** pylablib.core.thread.callsync.QDummyResultSynchronizer

Bases: [object](#)

Dummy result synchronizer for call which don't require result synchronization (e.g., multicasts)

**notify(value)**

**class** pylablib.core.thread.callsync.QDirectResultSynchronizer(value)

Bases: [object](#)

Result "synchronizer" for direct calls.

Behaves as a regular result synchronizer with an already executed call.

**get\_progress()**

Get the progress of the call execution (always return "done")

**is\_call\_done()**

Check if the call is done (always return True)

**skipped()**

Check if the call was skipped (always return False)

**failed()**

Check if the call failed (always return False)

**get\_value()**

Return stored value

**get\_value\_sync**(timeout=None, default=None, error\_on\_fail=True, error\_on\_skip=True, pass\_exception=True)

Return stored value.

Parameters are only for compatibility with [QCallResultSynchronizer](#).

**wait(\*args, \*\*kwargs)**

Do nothing (present only for compatibility with [QCallResultSynchronizer](#))

**notify(\*args, \*\*kwargs)**

Do nothing (present only for compatibility with [QCallResultSynchronizer](#))

**waiting()**

Check if waiting is in progress (always return False)

**done\_wait()**

Check if waiting is done (always return True)

**success\_wait()**

Check if waiting is done successfully (always return True)

**done\_notify()**

Check if notifying is done (always return True)

**waiting\_state()**

**notifying\_state()**

**class** `pylablib.core.thread.callsync.QScheduledCall`(*func*, *args=None*, *kwargs=None*, *silent=False*, *result\_synchronizer=None*)

Bases: `object`

Object representing a scheduled remote call.

Can be executed, skipped, or failed in the target thread, in which case it notifies the result synchronizer (if supplied).

#### Parameters

- **func** – callable to be invoked in the destination thread
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **silent** – if True, silence the exception in the execution thread and simply pass it to the caller thread; otherwise, the exception is raised in both threads
- **result\_synchronizer** – result synchronizer object; can be None (create new `QCallResultSynchronizer`), "async" (no result synchronization), or a `QCallResultSynchronizer` object.

**class** `Callback`(*func*, *pass\_result*, *call\_on\_exception*, *call\_on\_unschedule*)

Bases: `tuple`

**call\_on\_exception**

**call\_on\_unschedule**

**func**

**pass\_result**

**execute**(*silent=None*)

Execute the call and notify the result synchronizer (invoked by the destination thread)

**add\_callback**(*callback*, *pass\_result=True*, *call\_on\_exception=False*, *call\_on\_unschedule=False*, *front=False*)

Set the callback to be executed after the main call is done.

If `pass_result==True`, pass function result to the callback (or None if call failed); otherwise, pass no arguments. If `call_on_exception==True`, call it even if the original call raised an exception. If `call_on_unschedule==True`, call it for any call unscheduling event, including using `skip()` or `fail()` methods (this effectively ignores `call_on_exception`, since the callback is called regardless of the exception). If `front==True`, add the callback in the front of the line (executes first).



**fail()**

Notify that the call is failed (invoked by the destination thread)

**skip()**

Notify that the call is skipped (invoked by the destination thread)

**class** pylablib.core.thread.callsync.TDefaultCallInfo(*call\_time*)

Bases: [tuple](#)

**call\_time**

**class** pylablib.core.thread.callsync.QScheduler(*call\_info\_argname=None*)

Bases: [object](#)

Generic call scheduler.

Two methods are used by the external scheduling routines: [build\\_call\(\)](#) to create a [QScheduledCall](#) with appropriate parameters, and [schedule\(\)](#), which takes a call and schedules it. The [schedule\(\)](#) method should return True if the scheduling was successful (at least, for now), and False otherwise.

#### Parameters

**call\_info\_argname** – if not None, supplies a name of a keyword argument via which call info (generated by [build\\_call\\_info\(\)](#)) is passed on function call

**build\_call\_info()**

Build call info tuple which can be passed to scheduled calls

**build\_call**(*func, args=None, kwargs=None, callback=None, pass\_result=True, callback\_on\_exception=True, sync\_result=True*)

Build [QScheduledCall](#) for subsequent scheduling.

#### Parameters

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if True, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if True, execute the callback on call fail or skip (if it requires an argument, None is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if True, the call has a default result synchronizer; otherwise, no synchronization is made.

**schedule**(*call*)

Schedule the call

**clear()**

Clear the scheduler

**class** pylablib.core.thread.callsync.QDirectCallScheduler(*call\_info\_argname=None*)

Bases: [QScheduler](#)

Simplest call scheduler: directly executes the calls on scheduling in the scheduling thread.

**Parameters**

**call\_info\_argname** – if not `None`, supplies a name of a keyword argument via which call info (generated by `QScheduler.build_call_info()`) is passed on function call

**build\_call**(*func*, *args=None*, *kwargs=None*, *callback=None*, *pass\_result=True*, *callback\_on\_exception=True*, *sync\_result=False*)

Build `QScheduledCall` for subsequent scheduling.

**Parameters**

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if `True`, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if `True`, execute the callback on call fail or skip (if it requires an argument, `None` is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if `True`, the call has a default result synchronizer; otherwise, no synchronization is made.

**schedule**(*call*)

Schedule the call

**build\_call\_info**()

Build call info tuple which can be passed to scheduled calls

**clear**()

Clear the scheduler

**class** `pylablib.core.thread.callsync.QQueueScheduler`(*on\_full\_queue='skip\_current'*, *call\_info\_argname=None*)

Bases: `QScheduler`

Call scheduler with a builtin call queue.

Supports placing the calls and retrieving them (from the destination thread). Has ability to skip some calls if, e.g., the queue is too full. Whether the call should be skipped is determined by `can_schedule()` (should be overloaded in subclasses). Used as a default command scheduler.

**Parameters**

- **on\_full\_queue** – action to be taken if the call can't be scheduled (i.e., `can_schedule()` returns `False`); can be `"skip_current"` (skip the call which is being scheduled), `"skip_newest"` (skip the most recent call; place the current), `"skip_oldest"` (skip the oldest call in the queue; place the current), `"call_current"` (execute the call which is being scheduled immediately in the caller thread), `"call_newest"` (execute the most recent call immediately in the caller thread), `"call_oldest"` (execute the oldest call in the queue immediately in the caller thread), or `"wait"` (wait until the call can be scheduled, which is checked after every call removal from the queue; place the call)
- **call\_info\_argname** – if not `None`, supplies a name of a keyword argument via which call info (generated by `QScheduler.build_call_info()`) is passed on function call

**Methods to overload:**

- `can_schedule()`: check if the call can be scheduled
- `call_added()`: called when a new call has been added to the queue
- `call_popped()`: called when a call has been removed from the queue (either for execution, or for skipping)

**can\_schedule**(*call*)

Check if the call can be scheduled

**call\_added**(*call*)

Called whenever *call* has been added to the queue

**call\_popped**(*call*, *idx*)

Called whenever *call* has been removed from the queue

*idx* determines the call position within the queue.

**schedule**(*call*)

Schedule a call

**pop\_call**()

Pop the call from the queue head.

If the queue is empty, return None

**unschedule**(*call*)

Unschedule a given call.

Designed for joint queue operation, so the call is not notified (assume that it has been already notified elsewhere).

**has\_calls**()

Check if there are queued calls

**clear**(*close=True*)

Clear the call queue.

If *close==True*, mark the queue as closed (any attempt to schedule more calls fails automatically) and fail all calls in the queue; otherwise, skip all calls currently in the queue.

**build\_call**(*func*, *args=None*, *kwargs=None*, *callback=None*, *pass\_result=True*,  
*callback\_on\_exception=True*, *sync\_result=True*)

Build *QScheduledCall* for subsequent scheduling.

#### Parameters

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if *True*, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if *True*, execute the callback on call fail or skip (if it requires an argument, *None* is supplied); otherwise, only execute it if the call was successful

- **sync\_result** – if True, the call has a default result synchronizer; otherwise, no synchronization is made.

**build\_call\_info()**

Build call info tuple which can be passed to scheduled calls

```
class pylablib.core.thread.callsync.QQueueLengthLimitScheduler(max_len=1,  
                                                                on_full_queue='skip_current',  
                                                                call_info_argname=None)
```

Bases: [QQueueScheduler](#)

Queued call scheduler with a length limit.

#### Parameters

- **max\_len** – maximal queue length; non-positive values are interpreted as no limit can also be a tuple (arg\_name, max\_len), in which case the length is calculated separately for every value of the parameter arg\_name supplied to the method
- **on\_full\_queue** – action to be taken if the call can't be scheduled (the queue is full); can be "skip\_current" (skip the call which is being scheduled), "skip\_newest" (skip the most recent call; place the current), "skip\_oldest" (skip the oldest call in the queue; place the current), "call\_current" (execute the call which is being scheduled immediately in the caller thread), "call\_newest" (execute the most recent call immediately in the caller thread), "call\_oldest" (execute the oldest call in the queue immediately in the caller thread), or "wait" (wait until the call can be scheduled, which is checked after every call removal from the queue; place the call)
- **call\_info\_argname** – if not None, supplies a name of a keyword argument via which call info (generated by [QScheduler.build\\_call\\_info\(\)](#)) is passed on function call

**change\_max\_len(max\_len)**

Change maximal length of the call queue (doesn't affect already scheduled calls)

**get\_current\_len()**

Get current number of calls in the queue

**call\_added(call)**

Called whenever *call* has been added to the queue

**call\_popped(call, idx)**

Called whenever *call* has been removed from the queue

*idx* determines the call position within the queue.

**can\_schedule(call)**

Check if the call can be scheduled

```
build_call(func, args=None, kwargs=None, callback=None, pass_result=True,  
            callback_on_exception=True, sync_result=True)
```

Build [QScheduledCall](#) for subsequent scheduling.

#### Parameters

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done

- **pass\_result** (*bool*) – if True, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if True, execute the callback on call fail or skip (if it requires an argument, None is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if True, the call has a default result synchronizer; otherwise, no synchronization is made.

**build\_call\_info()**

Build call info tuple which can be passed to scheduled calls

**clear**(*close=True*)

Clear the call queue.

If *close==True*, mark the queue as closed (any attempt to schedule more calls fails automatically) and fail all calls in the queue; otherwise, skip all calls currently in the queue.

**has\_calls()**

Check if there are queued calls

**pop\_call()**

Pop the call from the queue head.

If the queue is empty, return None

**schedule**(*call*)

Schedule a call

**unschedule**(*call*)

Unschedule a given call.

Designed for joint queue operation, so the call is not notified (assume that it has been already notified elsewhere).

```
class pylablib.core.thread.callsync.QQueueSizeLimitScheduler(max_size=1, size_calc=None,  
                                                           on_full_queue='skip_current',  
                                                           call_info_argname=None)
```

Bases: [QQueueScheduler](#)

Queued call scheduler with a generic size limit; similar to [QQueueLengthLimitScheduler](#), but more flexible and can implement more restrictions (e.g., queue length and arguments RAM size).

**Parameters**

- **max\_size** – maximal total size of the arguments; can be either a single number, or a tuple (if several different size metrics are involved); non-positive values are interpreted as no limit
- **size\_calc** – function that takes a single argument (call to be placed) and returns its size; can be either a single number, or a tuple (if several different size metrics are involved); by default, simply returns 1, which makes the scheduler behavior identical to [QQueueLengthLimitScheduler](#)
- **on\_full\_queue** – action to be taken if the call can't be scheduled (the queue is full); can be "skip\_current" (skip the call which is being scheduled), "skip\_newest" (skip the most recent call; place the current), "skip\_oldest" (skip the oldest call in the queue; place the current), "call\_current" (execute the call which is being scheduled immediately in the caller thread), "call\_newest" (execute the most recent call immediately in the caller thread), "call\_oldest" (execute the oldest call in the queue immediately in

the caller thread), or "wait" (wait until the call can be scheduled, which is checked after every call removal from the queue; place the call)

- **call\_info\_argname** – if not `None`, supplies a name of a keyword argument via which call info (generated by `QScheduler.build_call_info()`) is passed on function call

**change\_max\_size**(*max\_size*)

Change size restrictions

**get\_current\_size**()

Get current size metrics

**call\_added**(*call*)

Called whenever *call* has been added to the queue

**call\_popped**(*call*, *idx*)

Called whenever *call* has been removed from the queue

*idx* determines the call position within the queue.

**can\_schedule**(*call*)

Check if the call can be scheduled

**build\_call**(*func*, *args=None*, *kwargs=None*, *callback=None*, *pass\_result=True*,  
*callback\_on\_exception=True*, *sync\_result=True*)

Build [QScheduledCall](#) for subsequent scheduling.

#### Parameters

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if `True`, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if `True`, execute the callback on call fail or skip (if it requires an argument, `None` is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if `True`, the call has a default result synchronizer; otherwise, no synchronization is made.

**build\_call\_info**()

Build call info tuple which can be passed to scheduled calls

**clear**(*close=True*)

Clear the call queue.

If `close==True`, mark the queue as closed (any attempt to schedule more calls fails automatically) and fail all calls in the queue; otherwise, skip all calls currently in the queue.

**has\_calls**()

Check if there are queued calls

**pop\_call()**

Pop the call from the queue head.

If the queue is empty, return None

**schedule(call)**

Schedule a call

**unschedule(call)**

Unschedule a given call.

Designed for joint queue operation, so the call is not notified (assume that it has been already notified elsewhere).

**pylablib.core.thread.callsync.schedule\_multiple\_queues(call, queues)**

Schedule the call simultaneously in several queues.

Go through queues in the given order and schedule call in every one of them. If one of the schedules failed or the call has been executed there, unschedule it from all the previous queues and return False; otherwise, return True.

**class pylablib.core.thread.callsync.QMultiQueueScheduler(schedulers, notifiers)**

Bases: [object](#)

Wrapper around [schedule\\_multiple\\_queues\(\)](#) which acts as a single scheduler.

Support additional notifiers, which are called if the scheduling is successful (e.g., to notify and wake up the destination thread).

**build\_call(\*args, \*\*kwargs)**

**schedule(call)**

**class pylablib.core.thread.callsync.QThreadCallScheduler(thread=None, tag=None, priority=0, interrupt=True, call\_info\_argname=None)**

Bases: [QScheduler](#)

Call scheduler via thread calls ([QThreadController.call\\_in\\_thread\\_callback\(\)](#))

#### Parameters

- **thread** – destination thread (by default, thread which creates the scheduler)
- **tag** – if supplied, send the call in a message with the given tag; otherwise, use the interrupt call (generally, higher priority method).
- **priority** – message priority (only when *tag* is not None)
- **interrupt** – whether the call is an interrupt (call inside any loop, e.g., during waiting or sleeping), or it should be called in the main event loop
- **call\_info\_argname** – if not None, supplies a name of a keyword argument via which call info (generated by [QScheduler.build\\_call\\_info\(\)](#)) is passed on function call

**schedule(call)**

Schedule the call

**build\_call(func, args=None, kwargs=None, callback=None, pass\_result=True, callback\_on\_exception=True, sync\_result=True)**

Build [QScheduledCall](#) for subsequent scheduling.

**Parameters**

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*
- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if True, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if True, execute the callback on call fail or skip (if it requires an argument, None is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if True, the call has a default result synchronizer; otherwise, no synchronization is made.

**build\_call\_info()**

Build call info tuple which can be passed to scheduled calls

**clear()**

Clear the scheduler

```
class pylablib.core.thread.callsync.QMulticastThreadCallScheduler(thread=None, limit_queue=1,
                                                                    tag=None, priority=0,
                                                                    interrupt=True,
                                                                    call_info_argname=None)
```

Bases: [QThreadCallScheduler](#)

Extended call scheduler via thread calls, which can limit number of queued calls.

**Parameters**

- **thread** – destination thread (by default, thread which creates the scheduler)
- **limit\_queue** – call queue limit (non-positive numbers are interpreted as no limit)
- **tag** – if supplied, send the call in a message with the given tag; otherwise, use the interrupt call (generally, higher priority method).
- **priority** – message priority (only when *tag* is not None)
- **interrupt** – whether the call is an interrupt (call inside any loop, e.g., during waiting or sleeping), or it should be called in the main event loop
- **call\_info\_argname** – if not None, supplies a name of a keyword argument via which call info (generated by [QScheduler.build\\_call\\_info\(\)](#)) is passed on function call

**schedule(call)**

Schedule the call

```
build_call(func, args=None, kwargs=None, callback=None, pass_result=True,
           callback_on_exception=True, sync_result=True)
```

Build [QScheduledCall](#) for subsequent scheduling.**Parameters**

- **func** – function to be called
- **args** – arguments to be passed to *func*
- **kwargs** – keyword arguments to be passed to *func*



- **callback** – optional callback to be called when *func* is done
- **pass\_result** (*bool*) – if True, pass *func* result as a single argument to the callback; otherwise, give no arguments
- **callback\_on\_exception** (*bool*) – if True, execute the callback on call fail or skip (if it requires an argument, None is supplied); otherwise, only execute it if the call was successful
- **sync\_result** – if True, the call has a default result synchronizer; otherwise, no synchronization is made.

**build\_call\_info()**

Build call info tuple which can be passed to scheduled calls

**clear()**

Clear the scheduler

### pylablib.core.thread.controller module

`pylablib.core.thread.controller.exint(error_msg_template='{ }:', pass_stop_exception=False)`

Context that intercepts exceptions and stops the execution in a controlled manner (quitting the main thread)

`pylablib.core.thread.controller.add_exception_hook(name, func, single_call=False)`

Add an exception hook, which is called whenever exception is caught via `exint()` wrapper.

If `single_call==True`, the hook is removed from the set when it is called.

`pylablib.core.thread.controller.remove_exception_hook(name)`

Remove the exception hook with the given name

`pylablib.core.thread.controller.exsafe(func)`

Decorator that intercepts exceptions raised by *func* and stops the execution in a controlled manner (quitting the main thread)

`pylablib.core.thread.controller.exsafeSlot(*slargs, **slkwargs)`

Wrapper around Qt slot which intercepts exceptions and stops the execution in a controlled manner

`pylablib.core.thread.controller.toploopSlot(*slargs, **slkwargs)`

Wrapper around Qt slot which intercepts exceptions and stops the execution in a controlled manner

`class pylablib.core.thread.controller.QThreadControllerThread(controller)`

Bases: `object`

`finalized = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>`

`run()`

`quit_sync()`

`pylablib.core.thread.controller.remote_call(func)`

Decorator that turns a controller method into a remote call (call from a different thread is passed synchronously)

`pylablib.core.thread.controller.call_in_thread(thread_name, interrupt=True, pass_exception=True, silent=False, sync=True)`

Decorator that turns any function into a remote call in a thread with a given name (call from a different thread is passed synchronously)

```
pylablib.core.thread.controller.call_in_gui_thread(func=None, interrupt=True,  
                                                  pass_exception=True, silent=False, sync=True)
```

Decorator that turns any function into a remote call in a GUI thread (call from a different thread is passed synchronously)

```
pylablib.core.thread.controller.gui_thread_method(func)
```

Decorator for an object's method that checks if the object's `gui_thread_safe` attribute is true, in which case the call is routed to the GUI thread

```
class pylablib.core.thread.controller.QThreadController(name=None, kind='loop',  
                                                         multicast_pool=None)
```

Bases: `object`

Generic Qt thread controller.

Responsible for all inter-thread synchronization. There is one controller per thread, and

#### Parameters

- **name** (*str*) – thread name (by default, generate a new unique name); this name can be used to obtain thread controller via `get_controller()`
- **kind** (*str*) – thread kind; can be "loop" (thread is running in the Qt message loop; behavior is implemented in `process_message()` and remote calls), "run" (thread executes `run()` method and quits after it is complete), or "main" (can only be created in the main GUI thread)
- **multicast\_pool** – `MulticastPool` for this thread (by default, use the default common pool)

#### Methods to overload:

- `on_start()`: executed on the thread startup (between synchronization points "start" and "run")
- `on_finish()`: executed on thread cleanup (attempts to execute in any case, including exceptions)
- `run()`: executed once per thread; thread is stopped afterwards (only if `kind=="run"`)
- `process_message()`: function that takes 2 arguments (tag and value) of the message and processes it; returns True if the message has been processed and False otherwise (in which case it is stored and can be recovered via `wait_for_message()/pop_message()`; by default, always return False
- `process_interrupt()`: function that takes 2 arguments (tag and value) of the interrupt message (message with a tag starting with "interrupt.") and processes it; by default, assumes that any value with tag "execute" is a function and executes it

#### Signals:

- started: emitted on thread start (after `on_start()` is executed)
- finished: emitted on thread finish (before `on_finish()` is executed)

```
started = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>
```

This signal is emitted after the thread has started (after the setup code has been executed, before its lifetime state is changed)

```
finished = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>
```

This signal is emitted before the thread has finished (before the cleanup code has been executed, after its lifetime state is changed)

**allowing\_toploop**(*depth=1*)

Context manager which temporarily treats the current loop level and several deeper levels as a top loop.

All event loops which lie up to *depth* below this one are treated as top loops.

**blocking\_control\_signals**(*kinds='all', ignore=None*)

Context manager which temporarily blocks external control signals.

After leaving the wrapped code segment, all of the blocked but not ignored calls are executed. *kind* determines the kind of calls to block; it is a collection of elements among "message", "stop", and "call" and blocks, correspondingly, messages, stop signals, and any *call\_in\_thread*-related requests; can be also be "all", which includes all of these categories. *ignore* specifies kinds which are completely ignored if sent during the blocking interval; can also be "all", which includes all of the *kinds* categories. Useful to temporarily “suspend” the thread communication with other threads, especially for the main GUI thread (e.g., to show a blocking message box). Local call method.

**wait\_for\_message**(*tag, timeout=None, top\_loop=False*)

Wait for a single message with a given tag.

Return value of a received message with this tag. If timeout is passed, raise *threadprop.TimeoutThreadError*. If *top\_loop==True*, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**new\_messages\_number**(*tag*)

Get the number of queued messages with a given tag.

Local call method.

**pop\_message**(*tag*)

Pop the latest message with the given tag.

Select the message with the highest priority, and among those the oldest one. If no messages are available, raise *threadprop.NoMessageThreadError*. Local call method.

**wait\_for\_sync**(*tag, uid, timeout=None*)

Wait for synchronization signal with the given tag and UID.

This method is rarely invoked directly, and is usually used by synchronizers code. If timeout is passed, raise *threadprop.TimeoutThreadError*. Local call method.

**wait\_for\_any\_message**(*timeout=None, top\_loop=False*)

Wait for any message (including synchronization messages or pokes).

If timeout is passed, raise *threadprop.TimeoutThreadError*. If *top\_loop==True*, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**wait\_until**(*check, timeout=None, top\_loop=False*)

Wait until a given condition is true.

Condition is given by the *check* function, which is called after every new received message and should return True if the condition is met. If *top\_loop==True*, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). If timeout is passed, raise *threadprop.TimeoutThreadError*. Local call method.

**check\_messages**(*top\_loop=False*)

Receive new messages.

Runs the underlying message loop to process newly received message and signals (and place them in corresponding queues if necessary). This method is rarely invoked, and only should be used periodically during long computations to not ‘freeze’ the thread. If *top\_loop==True*, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**sleep**(*timeout*, *wake\_on\_message=False*, *top\_loop=False*)

Sleep for a given time (in seconds).

Unlike `time.sleep()`, constantly checks the event loop for new messages (e.g., if stop or interrupt commands are issued). In addition, if `wake_on_message==True`, wake up if any message has been received; if this case, return `True` if the wait has been completed, and `False` if it has been interrupted by a message. If `top_loop==True`, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). If `timeout` is `None`, wait forever (usually, until the application is closed, or some interrupt message raises an error). Local call method.

**no\_stopping()**

Context manager, which temporarily suspends stop requests (`InterruptExceptionStop` exceptions).

If the stop request has been made within this block, raise the exception on exit. Note that `stop()` method and, correspondingly, `stop_controller()` still work, when called from the controlled thread.

**process\_interrupt**(*tag*, *value*)

Process a new interrupt.

If the function returns `False`, the interrupt is put in the corresponding queue. Otherwise, the message is interrupt to be already, and it gets 'absorbed'. Local call method, called automatically.

**process\_message**(*tag*, *value*)

Process a new message.

If the function returns `False`, the message is put in the corresponding queue. Otherwise, the message is considered to be already, and it gets 'absorbed'. Local call method, called automatically.

**on\_start()**

Method invoked on the start of the thread.

Local call method, called automatically.

**on\_finish()**

Method invoked in the end of the thread.

Called regardless of the stopping reason (normal finishing, exception, application finishing). Local call method, called automatically.

**run()**

Method called to run the main thread code (only for "run" thread kind).

Local call method, called automatically.

**subscribe\_sync**(*callback*, *srcs='any'*, *tags=None*, *dsts='any'*, *filt=None*, *subscription\_priority=0*, *limit\_queue=None*, *call\_interrupt=True*, *add\_call\_info=False*, *return\_result=False*, *sid=None*)

Subscribe a synchronous callback to a multicast.

If a multicast is sent, *callback* is called from the *dest\_controller* thread (by default, thread which is calling this function) via the thread call mechanism (`QThreadController.call_in_thread_callback()`). In Qt, analogous to making a signal connection with a queued call. By default, the subscribed destination is the thread's name. Local call method.

#### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or *[str]*) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).

- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **subscription\_priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **limit\_queue** (*int*) – limits the maximal number of scheduled calls (if the multicast is sent while at least *limit\_queue* callbacks are already in queue to be executed, ignore it) 0 or negative value means no limit (not recommended, as it can increase the queue indefinitely if the multicast rate is high enough)
- **call\_interrupt** – whether the call is an interrupt (call inside any loop, e.g., during waiting or sleeping), or it should be called in the main event loop
- **add\_call\_info** (*bool*) – if True, add a fourth argument containing a call information (tuple with a single element, a timestamps of the call).
- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique name).

**subscribe\_direct** (*callback*, *srcs*='any', *tags*=None, *dsts*='any', *filt*=None, *subscription\_priority*=0, *scheduler*=None, *return\_result*=False, *sid*=None)

Subscribe asynchronous callback to a multicast.

If a multicast is sent, *callback* is called from the sending thread (not subscribed thread). Therefore, should be used with care. In Qt, analogous to making a signal connection with a direct call. By default, the subscribed destination is the thread's name. Local call method.

#### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or [*str*]) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).
- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **subscription\_priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **scheduler** – if defined, multicast call gets scheduled using this scheduler instead of being called directly (which is the default behavior)

- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique id and return it).

#### **unsubscribe**(*sid*)

Unsubscribe from a subscription with a given ID.

Note that multicasts which are already emitted but not processed will remain in the queue; if they need to be ignored, it should be handled explicitly. Local call method.

#### **send\_multicast**(*dst='any', tag=None, value=None, src=None, filter\_results=True*)

Send a multicast to the multicast pool.

By default, the multicast source is the thread's name. Return result synchronizers for all executed subscribed methods. Local call method.

##### **Parameters**

- **dst** (*str*) – multicast destination; can be a name, "all" (will pass all subscribers' destination filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" destination).
- **tag** (*str*) – multicast tag.
- **value** – multicast value.
- **src** (*str*) – multicast source; can be None (current thread name), a specific name, "all" (will pass all subscribers' source filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" source).
- **filter\_results** – if True, filter the results to exclude dummy synchronizers, which correspond to calls which do not return anything

#### **send\_multicast\_sync**(*dst='any', tag=None, value=None, src=None, timeout=None, default\_result=None, pass\_exception=True*)

Send a multicast to the multicast pool and synchronize the results, if available.

By default, the multicast source is the thread's name. Results are collected and synchronized only from the subscriptions which return them (i.e., set `return_result=True`). Local call method.

##### **Parameters**

- **dst** (*str*) – multicast destination; can be a name, "all" (will pass all subscribers' destination filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" destination).
- **tag** (*str*) – multicast tag.
- **value** – multicast value.
- **src** (*str*) – multicast source; can be None (current thread name), a specific name, "all" (will pass all subscribers' source filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" source).
- **timeout** – synchronization timeout (None means waiting forever)
- **default\_result** – default result value if synchronization failed (timed out, thread stopped, etc.)
- **pass\_exception** – if True and the signal processor raised an exception, raise it in this thread as well. If `pass_exception==True` and the returned value represents exception, re-raise it in the caller thread; otherwise, return *default*.

**set\_variable**(*name*, *value*, *update=False*, *notify=False*, *notify\_tag='changed/\*'*, *simple=False*)

Set thread variable.

Can be called in any thread (controlled or external). If `notify==True`, send an multicast with the given `notify_tag` (where "\*" symbol is replaced by the variable name). If `update==True` and the value is a dictionary, update the branch rather than overwrite it. If `simple==True`, assume that the result is a single atomic variable, in which case the lock is not used; note that in this case the threads waiting on this variable (or branches containing it) will not be notified. Local call method.

**delete\_variable**(*name*, *missing\_error=False*)

Delete thread variable.

If `missing_error==False` and no variable exists, do nothing; otherwise, raise an error. Local call method.

**set\_func\_variable**(*name*, *func*, *use\_lock=True*)

Set a 'function' variable.

Acts as a thread variable to the external user, but instead of reading a stored value, it executed a function instead. Note, that the function is executed in the caller thread (i.e., the thread which tries to access the variable), so use of synchronization methods (commands, signals, locks) is highly advised.

If `use_lock==True`, then the function call will be wrapped into the usual variable lock, i.e., it won't run concurrently with other variable access. Local call method.

**add\_thread\_method**(*name*, *method*, *interrupt=True*)

Add a thread method.

Adds a named method to the thread, which can be called later using `call_thread_method()`. This method will be called in this thread.

Useful for GUI thread to set up some global access methods, which other threads can safely use. For `QThread` threads it's a better idea to set up a command instead. Local call method.

**delete\_thread\_method**(*name*)

Delete a thread method.

Local call method.

**call\_thread\_method**(*name*, *\*args*, *\*\*kwargs*)

Call a thread method.

Method needs to be set up beforehand using `add_thread_method()`. It is always executed in the current thread. Local call method.

**send\_message**(*tag*, *value*, *priority=0*)

Send a message to the thread with a given tag, value and priority.

External call method.

**send\_interrupt**(*tag*, *value*, *priority=0*)

Send an interrupt message to the thread with a given tag, value and priority.

External call method.

**send\_sync**(*tag*, *uid*)

Send a synchronization signal with the given tag and UID.

This method is rarely invoked directly, and is usually used by synchronizers code (e.g., `QThreadNotifier`). External call method.



**get\_variable**(*name*, *default=None*, *copy\_branch=True*, *missing\_error=False*, *simple=False*)

Get thread variable.

If *missing\_error*==False and no variable exists, return *default*; otherwise, raise an error. If *copy\_branch*==True and the variable is a *Dictionary* branch, return its copy to ensure that it stays unaffected on possible further variable assignments. If *simple*==True, assume that the result is a single atomic variable, in which case the lock is not used; this only works with actual variables and not function variables. Universal call method.

**sync\_variable**(*name*, *pred*, *timeout=None*)

Wait until thread variable with the given *name* satisfies the condition given by *pred*.

*pred* can be a variable value, a container (list, set, tuple) of possible values, or a function which takes one argument (variable value) and returns whether the condition is satisfied. It is executed in the caller thread. External call method.

**start**()

Start the thread.

External call method.

**request\_stop**()

Request thread stop (send a stop command).

External call method.

**stop**(*code=0*, *sync=False*)

Stop the thread.

If called from the thread, stop immediately by raising a *threadprop.InterruptExceptionStop* exception. Otherwise, schedule thread stop. If the thread kind is "main", stop the whole application with the given exit code. Otherwise, stop the thread. If *sync*==True and the thread is not main or current, wait until it is completely stopped. Universal call method.

**sync\_stop**()

Wait until the controller and the thread are stopped.

External call method.

**poke**()

Send a dummy message to the thread.

A cheap way to notify the thread that something happened (useful for, e.g., making thread leave *wait\_for\_any\_message()* method). External call method.

**running**()

Check if the thread is running

**finishing**()

Check if the thread is finishing

**notify\_exec\_point**(*point*)

Mark the given execution point as passed.

Automatically invoked points include "start" (thread starting), "run" (thread setup and ready to run), "cleanup" (thread stopping is invoked, starting to clean up) and "stop" (thread finished). Can be extended for arbitrary points. Local call method.



**fail\_exec\_point**(*point*)

Mark the given execution point as failed.

Automatically invoked for "run" (thread setup and ready to run) if the startup raised an error before the thread properly started ("start", "cleanup", and "stop" are notified in any case) Can be extended for arbitrary points. Local call method.

**get\_exec\_counter**(*point*)

Get the counter (number of notifications) for the given point.

See [sync\\_exec\\_point\(\)](#) for details. External call.

**sync\_exec\_point**(*point*, *timeout=None*, *counter=1*)

Wait for the given execution point.

Automatically invoked points include "start" (thread starting), "run" (thread setup and ready to run), "cleanup" (thread stopping is invoked, starting to clean up) and "stop" (thread finished). If timeout is passed, raise [threadprop.TimeoutThreadError](#). *counter* specifies the minimal number of pre-requisite [notify\\_exec\\_point\(\)](#) calls to finish the waiting (by default, a single call is enough). Return actual number of notifier calls up to date. External call method.

**add\_stop\_notifier**(*func*, *call\_if\_stopped=True*)

Add stop notifier: a function which is called when the thread is about to be stopped (left the main message loop).

The supplied function is called in the controlled thread close to its shutdown, so it should be short, non-blocking, and thread-safe. If the thread is already stopped and *call\_if\_stopped==True*, call *func* immediately (from the caller's thread). Return *True* if the thread is still running and the notifier is added, and *False* otherwise. Local call method.

**remove\_stop\_notifier**(*func*)

Remove the stop notifier from this controller.

Return *True* if the notifier was in this thread and is now removed, and *False* otherwise. Local call method.

**is\_in\_controlled**()

Check if the thread executing this code is controlled by this controller

**call\_in\_thread\_callback**(*func*, *args=None*, *kwargs=None*, *callback=None*, *tag=None*, *priority=0*, *interrupt=True*)

Call a function in this thread with the given arguments.

If *callback* is supplied, call it with the result as a single argument (call happens in the controller thread). If *tag* is supplied, send the call in a message with the given tag; otherwise, use the interrupt call (generally, higher priority method). If *interrupt==True*, method can be called inside any control loop (either main loop, or during waiting); otherwise, only call it in the top loop. Universal call method.

**call\_in\_thread\_sync**(*func*, *args=None*, *kwargs=None*, *sync=True*, *callback=None*, *timeout=None*, *default\_result=None*, *pass\_exception=True*, *silent=False*, *tag=None*, *priority=0*, *interrupt=True*, *error\_on\_stopped=True*, *same\_thread\_shortcut=True*)

Call a function in this thread with the given arguments.

If *sync==True*, calling thread is blocked until the controlled thread executes the function, and the function result is returned (in essence, the fact that the function executes in a different thread is transparent). Otherwise, exit call immediately, and return a synchronizer object ([QCallResultSynchronizer](#)), which can be used to check if the call is done (method *is\_done*) and obtain the result (method [QCallResultSynchronizer.get\\_value\\_sync\(\)](#)). If *callback* is not *None*, call it after the function is successfully executed (from the target thread), with a single parameter being function result. If *pass\_exception==True* and *func* raises an exception, re-raise it in the caller thread (applies only if

`sync==True`). If `silent==True` and `func` raises an exception, silence it in the execution thread and only re-raise it in the caller thread; note that if `pass_exception==False` and `silent==True`, the exception is ignored in both threads. If `tag` is supplied, send the call in a message with the given tag and priority; otherwise, use the interrupt call (generally, higher priority method). If `interrupt==True`, method can be called inside any control loop (either main loop, or during waiting); otherwise, only call it in the top loop. If `error_on_stopped==True` and the controlled thread is stopped before it executed the call, raise `threadprop.NoControllerThreadError`; otherwise, return `default_result`. If `same_thread_shortcut==True` (default), the call is synchronous, and the caller thread is the same as the controlled thread, call the function directly. Universal call method.

```
class pylablib.core.thread.controller.QTaskThread(name=None, args=None, kwargs=None,
                                                  multicast_pool=None)
```

Bases: `QThreadController`

Thread which allows to set up and run jobs and batch jobs with a certain time period, and execute commands in the meantime.

#### Parameters

- **name** (`str`) – thread name (by default, generate a new unique name)
- **args** – args supplied to `setup_task()` method
- **kwargs** – keyword args supplied to `setup_task()` method
- **multicast\_pool** – `MulticastPool` for this thread (by default, use the default common pool)

#### ca

asynchronous command accessor, which makes calls more function-like; `ctl.ca.comm(*args, **kwargs)` is equivalent to `ctl.call_command("comm", args, kwargs, sync=False)`

#### cai

asynchronous command accessor which ignores and silences any exceptions (including missing /stopped controller) useful for sending queries during thread finalizing / application shutdown, when it's not guaranteed that the command recipient is running `ctl.cai.comm(*args, **kwargs)` is equivalent to `ctl.call_command("comm", args, kwargs, sync=False, ignore_errors=True)`

#### cad

asynchronous command accessor returning a result synchronizer, which makes calls more function-like; `ctl.cad.comm(*args, **kwargs)` is equivalent to `ctl.call_command("comm", args, kwargs, sync="delayed")`

#### cs

synchronous command accessor, which makes calls more function-like; `ctl.cs.comm(*args, **kwargs)` is equivalent to `ctl.call_command("comm", args, kwargs, sync=True)`

#### css

synchronous command accessor which is made 'exception-safe' via `exsafe()` wrapper (i.e., safe to directly connect to slots) `ctl.css.comm(*args, **kwargs)` is equivalent to with `exint():` `ctl.call_command("comm", args, kwargs, sync=True)`

#### csi

synchronous command accessor which ignores and silences any exceptions (including missing /stopped controller) useful for sending queries during thread finalizing / application shutdown, when it's not guaranteed that the command recipient is running

**m**

method accessor; directly calls the method corresponding to the command; `ctl.m.comm(*args, **kwargs)` is equivalent to `ctl.call_command("comm", *args, **kwargs)`, which is often also equivalent to `ctl.comm(*args, **kwargs)`; for most practical purposes it's the same as directly invoking the class method, but it makes intent more explicit (as command methods are usually not called directly from other threads), and it doesn't invoke warning about calling method instead of command from another thread.

**Methods to overload:**

- `setup_task()`: executed on the thread startup (between synchronization points "start" and "run")
- `finalize_task()`: executed on thread cleanup (attempts to execute in any case, including exceptions)

**class** `TBatchJob(job, cleanup, min_run_time, priority)`

Bases: `tuple`

**cleanup**

**job**

**min\_run\_time**

**priority**

**class** `TCommand(command, scheduler, priority)`

Bases: `tuple`

**command**

**priority**

**scheduler**

**class** `Job(job, period, queue, jobs_order)`

Bases: `object`

A single job loop.

Deals with scheduling, time counting, pausing, and cleanup.

**Parameters**

- **job** – job function
- **period** – job period
- **queue** – thread controller's scheduling queue, to which the job must be added
- **jobs\_order** – thread controller's job queue which determines the jobs scheduling order

**schedule()**

Schedule the job

**mark\_unscheduled()**

Mark the job as unscheduled.

Called automatically on job completion.

**unschedule()**

Manually unschedule the job (e.g., when paused or removed)

**clear()**

Clear the job and remove it from the jobs list

**change\_period(*period*)**

Change the job period

**pause(*paused=True, unschedule=True*)**

Pause or resume the job.

If pausing and `unschedule==True`, remove already scheduled job from the queue.

**time\_left(*t=None*)**

Get the amount of time left till the next call, or `None` if the job is paused

**add\_job(*name, job, period, initial\_call=True, priority=-10*)**

Add a recurrent *job* which is called every *period* seconds.

The job starts running automatically when the main thread loop start executing. If `initial_call==True`, call *job* once immediately after adding. *priority* specifies the call priority in the scheduling queue; by default, it is lower than the command and multicasts (0). Local call method.

**change\_job\_period(*name, period*)**

Change the period of the job *name*.

Local call method.

**remove\_job(*name*)**

Remove the job *name* from the job list.

Local call method.

**add\_batch\_job(*name, job, cleanup=None, min\_runtime=0, priority=-10*)**

Add a batch *job* which is executed once, but with continuations.

After this call the job is just created, but is not running. To start it, call `start_batch_job()`. If specified, *cleanup* is a finalizing function which is called both when the job terminates normally, and when it is forcibly stopped (including thread termination). *min\_runtime* specifies minimal expected runtime of a job; if a job executes faster than this time, it is repeated again unless at least *min\_runtime* seconds passed; useful for high-throughput jobs, as it reduces overhead from the job scheduling mechanism (repeating within *min\_runtime* time window is fast)

Unlike the usual recurrent jobs, here *job* is a generator (usually defined by a function with `yield` statement). When the job is running, the generator is periodically called until it raises `StopIteration` exception, which signifies that the job is finished. From generator function point of view, after the job is started, the function is executed normally, but every time `yield` statement is encountered, the execution is suspended for *period* seconds (specified in `start_batch_job()`). *priority* specifies the call priority in the scheduling queue; by default, it is lower than the command and multicasts (0). Local call method.

**change\_batch\_job\_parameters(*name, job='keep', cleanup='keep', min\_runtime='keep', priority='keep', stop=False, restart=False*)**

Change parameters (main body, cleanup function, and minimal runtime) of the batch job.

The parameters are the same as for `add_batch_job()`. If any of them are "keep", don't change them. If `stop==True`, stop the job before changing the parameters; otherwise the job is continued with the previous parameters (including cleanup) until it is stopped and restarted. If `restart==True`, restart the job after changing the parameters. Local call method.

**remove\_batch\_job**(*name*)

Remove the batch job *name*, stopping it if necessary.

Local call method.

**start\_batch\_job**(*name*, *period*, \**args*, *start\_immediate=True*, \*\**kwargs*)

Start the batch job with the given name.

*period* specifies suspension period. Optional arguments are passed to the job and the cleanup functions. If *start\_immediate==True*, start the job (i.e., run the first iteration) immediately during the call; otherwise, start it only when it is scheduled, after the currently running call is complete. Local call method.

**is\_batch\_job\_running**(*name*)

Check if a given batch job running.

Local call method.

**stop\_batch\_job**(*name*, *stop\_immediate=True*, *error\_on\_stopped=False*)

Stop a given batch job.

If *error\_on\_stopped==True* and the job is not currently running, raise an error. Otherwise, do nothing. If *stop\_immediate==True*, stop the job (i.e., unschedule it and run the cleanup code) immediately during the call; otherwise, stop it when its next iteration is called. Local call method.

**restart\_batch\_job**(*name*, *start\_immediate=True*, *error\_on\_stopped=False*)

Restart the running batch job with its current arguments.

If *error\_on\_stopped==True* and the job is not currently running, raise an error. Otherwise, do nothing. Local call method.

**run\_as\_batch\_job**(*job*, *period*, *cleanup=None*, *name=None*, *priority=-10*, *start\_immediate=True*, *args=None*, *kwargs=None*)

Create a temporarily batch job and immediately run it.

If *name* is *None*, generate a new unique name. The job is removed after it is complete (i.e., after cleanup). Note that this implies, that it can not be restarted using [restart\\_batch\\_job\(\)](#), as it will be removed after the stopping before the restart. All the parameters are the same as for [add\\_batch\\_job\(\)](#) and [start\\_batch\\_job\(\)](#). Return the batch job name (either supplied or newly generated).

**run**()

Method called to run the main thread code (only for "run" thread kind).

Local call method, called automatically.

**on\_start**()

Method invoked on the start of the thread.

Local call method, called automatically.

**on\_finish**()

Method invoked in the end of the thread.

Called regardless of the stopping reason (normal finishing, exception, application finishing). Local call method, called automatically.

**setup\_task**(\**args*, \*\**kwargs*)

Setup the thread (called before the main task loop).

Local call method, called automatically.

**finalize\_task()**

Finalize the thread (always called on thread termination, regardless of the reason).

Local call method, called automatically.

**update\_status(*kind, status, text=None, notify=True*)**

Update status represented in thread variables.

*kind* is the status kind and *status* is its value. Status variable name is "status/"+*kind*. If *text* is not *None*, it specifies new status text stored in "status/"+*kind*+"\_text". If *notify*==*True*, send an multicast about the status change. Local call method.

**add\_command(*name, command=None, scheduler=None, limit\_queue=None, on\_full\_queue='skip\_current', priority=0*)**

Add a new command to the command set.

Return scheduler, which can be used for adding another command (if the same queue should be used for several commands). Local call method.

**Parameters**

- **name** – command name
- **command** – command function; if *None*, look for the method with the given *name*.
- **scheduler** – a command scheduler; by default, it is a [\*QQueueLengthLimitScheduler\*](#), which maintains a call queue with the given length limit and full queue behavior; can also be a name of a different command, with which it will share a single queue with the same limitations; if supplied, *limit\_queue* and *on\_full\_queue* parameters are ignored
- **limit\_queue** – command call queue limit; *None* means no limit
- **on\_full\_queue** – action to be taken if the call can't be scheduled (the queue is full); can be "skip\_current" (skip the call which is being scheduled), "skip\_newest" (skip the most recent call; place the current), "skip\_oldest" (skip the oldest call in the queue; place the current), "call\_current" (execute the call which is being scheduled immediately in the caller thread), "call\_newest" (execute the most recent call immediately in the caller thread), "call\_oldest" (execute the oldest call in the queue immediately in the caller thread), or "wait" (wait until the call can be scheduled, which is checked after every call removal from the queue; place the call)
- **priority** – command priority; higher-priority multicasts and commands are always executed before the lower-priority ones.

**add\_direct\_call\_command(*name, command=None, error\_on\_async=True*)**

Add a direct method call which appears as a command.

Unlike regular commands, the call is executed directly in the caller thread (i.e., it is identical to the direct method call). Useful for lightweight and/or lock-wrapped methods, which can be called in a thread-safe way, but which still use command interface for consistency. Note that this kind of commands doesn't have the same level of synchronization as regular commands (e.g., it can be executed during execution of another command, or commsync multicast method). Local call method.

**Parameters**

- **name** – command name
- **command** – command function; if *None*, look for the method with the given *name*.
- **error\_on\_async** – if *True* and the command is called asynchronously, raise an error; otherwise, substitute for a synchronous call

```
subscribe_commsync(callback, srcs='any', tags=None, dsts='any', filt=None, subscription_priority=0,
                    scheduler=None, limit_queue=None, on_full_queue='skip_current', priority=0,
                    add_call_info=False, return_result=False, sid=None)
```

Subscribe a callback to a multicast which is synchronized with commands and jobs execution.

Unlike the standard `QThreadController.subscribe_sync()` method, the subscribed callback will only be executed between jobs or commands, not during one of these. Local call method.

#### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or [*str*]) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).
- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **subscription\_priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **scheduler** – if defined, multicast call gets scheduled using this scheduler; by default, create a new call queue scheduler with the given *limit\_queue*, *on\_full\_queue* and *add\_call\_info* arguments.
- **limit\_queue** (*int*) – limits the maximal number of scheduled calls (if the multicast is sent while at least *limit\_queue* callbacks are already in queue to be executed, ignore it) 0 or negative value means no limit (not recommended, as it can increase the queue indefinitely if the multicast rate is high enough)
- **on\_full\_queue** – action to be taken if the call can't be scheduled (the queue is full); can be "skip\_current" (skip the call which is being scheduled), "skip\_newest" (skip the most recent call; place the current), "skip\_oldest" (skip the oldest call in the queue; place the current), "call\_current" (execute the call which is being scheduled immediately in the caller thread), "call\_newest" (execute the most recent call immediately in the caller thread), "call\_oldest" (execute the oldest call in the queue immediately in the caller thread), or "wait" (wait until the call can be scheduled, which is checked after every call removal from the queue; place the call)
- **add\_call\_info** (*bool*) – if True, add a fourth argument containing a call information (tuple with a single element, a timestamps of the call).
- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique id and return it).

```
call_command_direct(name, args=None, kwargs=None)
```

Invoke a command directly and immediately in the current thread.

Universal call method.



**call\_command**(*name*, *args=None*, *kwargs=None*, *sync=False*, *callback=None*, *timeout=None*, *ignore\_errors=False*)

Invoke command call with the given name and arguments

If *callback* is not *None*, call it after the command is successfully executed (from the target thread), with a single parameter being the command result. If *sync==True*, pause caller thread execution (for at most *timeout* seconds) until the command has been executed by the target thread, and then return the command result. If *sync=="delayed"*, return [QCallResultSynchronizer](#) object which can be used to wait for and read the command result; otherwise, return *None*. In the *sync==True* case, if *ignore\_errors==True*, ignore all possible problems with the call (controller stopped, call raised an exception, call was skipped) and return *None* instead; otherwise, these problems raise exceptions in the caller thread. Universal call method.

**call\_in\_thread\_commsync**(*func*, *args=None*, *kwargs=None*, *sync=True*, *timeout=None*, *priority=0*, *ignore\_errors=False*, *same\_thread\_shortcut=True*)

Call a function in this thread such that it is synchronous with other commands, and jobs.

Mostly equivalent to calling a command, only the command function is supplied instead of its name, and the advanced scheduling (maximal schedule size, sharing with different commands, etc.) is not used. *args* and *kwargs* specify the function arguments. If *sync==True*, pause caller thread execution (for at most *timeout* seconds) until the command has been executed by the target thread, and then return the command result. If *sync=="delayed"*, return [QCallResultSynchronizer](#) object which can be used to wait for and read the command result; otherwise, return *None*. *priority* sets the call priority (by default, the same as the standard commands). In the *sync==True* case, if *ignore\_errors==True*, ignore all possible problems with the call (controller stopped, call raised an exception, call was skipped) and return *None* instead; otherwise, these problems raise exceptions in the caller thread. If *same\_thread\_shortcut==True* (default) and the caller thread is the same as the controlled thread, call the function directly. Universal call method.

**comm\_paused()**

Context manager, which allows to temporarily pause all calls (commands, jobs, etc.)

**class CommandAccess**(*parent*, *sync*, *direct=False*, *timeout=None*, *safe=False*, *ignore\_errors=False*)

Bases: [object](#)

Accessor object designed to simplify command syntax.

Automatically created by the thread, so doesn't need to be invoked externally.

**add\_stop\_notifier**(*func*, *call\_if\_stopped=True*)

Add stop notifier: a function which is called when the thread is about to be stopped (left the main message loop).

The supplied function is called in the controlled thread close to its shutdown, so it should be short, non-blocking, and thread-safe. If the thread is already stopped and *call\_if\_stopped==True*, call *func* immediately (from the caller's thread). Return *True* if the thread is still running and the notifier is added, and *False* otherwise. Local call method.

**add\_thread\_method**(*name*, *method*, *interrupt=True*)

Add a thread method.

Adds a named method to the thread, which can be called later using [call\\_thread\\_method\(\)](#). This method will be called in this thread.

Useful for GUI thread to set up some global access methods, which other threads can safely use. For [QTaskThread](#) threads it's a better idea to set up a command instead. Local call method.

**allowing\_toploop**(*depth=1*)

Context manager which temporarily treats the current loop level and several deeper levels as a top loop.



All event loops which lie up to *depth* below this one are treated as top loops.

**blocking\_control\_signals**(*kinds*='all', *ignore*=None)

Context manager which temporarily blocks external control signals.

After leaving the wrapped code segment, all of the blocked but not ignored calls are executed. *kind* determines the kind of calls to block; it is a collection of elements among "message", "stop", and "call" and blocks, correspondingly, messages, stop signals, and any `call_in_thread`-related requests; can be also be "all", which includes all of these categories. *ignore* specifies kinds which are completely ignored if sent during the blocking interval; can also be "all", which includes all of the *kinds* categories. Useful to temporarily "suspend" the thread communication with other threads, especially for the main GUI thread (e.g., to show a blocking message box). Local call method.

**call\_in\_thread\_callback**(*func*, *args*=None, *kwargs*=None, *callback*=None, *tag*=None, *priority*=0, *interrupt*=True)

Call a function in this thread with the given arguments.

If *callback* is supplied, call it with the result as a single argument (call happens in the controller thread). If *tag* is supplied, send the call in a message with the given tag; otherwise, use the interrupt call (generally, higher priority method). If *interrupt*==True, method can be called inside any control loop (either main loop, or during waiting); otherwise, only call it in the top loop. Universal call method.

**call\_in\_thread\_sync**(*func*, *args*=None, *kwargs*=None, *sync*=True, *callback*=None, *timeout*=None, *default\_result*=None, *pass\_exception*=True, *silent*=False, *tag*=None, *priority*=0, *interrupt*=True, *error\_on\_stopped*=True, *same\_thread\_shortcut*=True)

Call a function in this thread with the given arguments.

If *sync*==True, calling thread is blocked until the controlled thread executes the function, and the function result is returned (in essence, the fact that the function executes in a different thread is transparent). Otherwise, exit call immediately, and return a synchronizer object (`QCallResultSynchronizer`), which can be used to check if the call is done (method `is_done`) and obtain the result (method `QCallResultSynchronizer.get_value_sync()`). If *callback* is not None, call it after the function is successfully executed (from the target thread), with a single parameter being function result. If *pass\_exception*==True and *func* raises an exception, re-raise it in the caller thread (applies only if *sync*==True). If *silent*==True and *func* raises an exception, silence it in the execution thread and only re-raise it in the caller thread; note that if *pass\_exception*==False and *silent*==True, the exception is ignored in both threads. If *tag* is supplied, send the call in a message with the given tag and priority; otherwise, use the interrupt call (generally, higher priority method). If *interrupt*==True, method can be called inside any control loop (either main loop, or during waiting); otherwise, only call it in the top loop. If *error\_on\_stopped*==True and the controlled thread is stopped before it executed the call, raise `threadprop.NoControllerThreadError`; otherwise, return *default\_result*. If *same\_thread\_shortcut*==True (default), the call is synchronous, and the caller thread is the same as the controlled thread, call the function directly. Universal call method.

**call\_thread\_method**(*name*, \**args*, \*\**kwargs*)

Call a thread method.

Method needs to be set up beforehand using `add_thread_method()`. It is always executed in the current thread. Local call method.

**check\_messages**(*top\_loop*=False)

Receive new messages.

Runs the underlying message loop to process newly received message and signals (and place them in corresponding queues if necessary). This method is rarely invoked, and only should be used periodically during long computations to not 'freeze' the thread. If *top\_loop*==True, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**delete\_thread\_method**(*name*)

Delete a thread method.

Local call method.

**delete\_variable**(*name*, *missing\_error=False*)

Delete thread variable.

If *missing\_error==False* and no variable exists, do nothing; otherwise, raise an error. Local call method.

**fail\_exec\_point**(*point*)

Mark the given execution point as failed.

Automatically invoked for "run" (thread setup and ready to run) if the startup raised an error before the thread properly started ("start", "cleanup", and "stop" are notified in any case) Can be extended for arbitrary points. Local call method.

**finished** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

This signal is emitted before the thread has finished (before the cleanup code has been executed, after its lifetime state is changed)

**finishing**()

Check if the thread is finishing

**get\_exec\_counter**(*point*)

Get the counter (number of notifications) for the given point.

See [sync\\_exec\\_point\(\)](#) for details. External call.

**get\_variable**(*name*, *default=None*, *copy\_branch=True*, *missing\_error=False*, *simple=False*)

Get thread variable.

If *missing\_error==False* and no variable exists, return *default*; otherwise, raise an error. If *copy\_branch==True* and the variable is a [Dictionary](#) branch, return its copy to ensure that it stays unaffected on possible further variable assignments. If *simple==True*, assume that the result is a single atomic variable, in which case the lock is not used; this only works with actual variables and not function variables. Universal call method.

**is\_in\_controlled**()

Check if the thread executing this code is controlled by this controller

**new\_messages\_number**(*tag*)

Get the number of queued messages with a given tag.

Local call method.

**no\_stopping**()

Context manager, which temporarily suspends stop requests ([InterruptExceptionStop](#) exceptions).

If the stop request has been made within this block, raise the exception on exit. Note that [stop\(\)](#) method and, correspondingly, [stop\\_controller\(\)](#) still work, when called from the controlled thread.

**notify\_exec\_point**(*point*)

Mark the given execution point as passed.

Automatically invoked points include "start" (thread starting), "run" (thread setup and ready to run), "cleanup" (thread stopping is invoked, starting to clean up) and "stop" (thread finished). Can be extended for arbitrary points. Local call method.

**poke()**

Send a dummy message to the thread.

A cheap way to notify the thread that something happened (useful for, e.g., making thread leave `wait_for_any_message()` method). External call method.

**pop\_message(tag)**

Pop the latest message with the given tag.

Select the message with the highest priority, and among those the oldest one. If no messages are available, raise `threadprop.NoMessageThreadError`. Local call method.

**process\_interrupt(tag, value)**

Process a new interrupt.

If the function returns `False`, the interrupt is put in the corresponding queue. Otherwise, the the message is interrupt to be already, and it gets 'absorbed'. Local call method, called automatically.

**process\_message(tag, value)**

Process a new message.

If the function returns `False`, the message is put in the corresponding queue. Otherwise, the the message is considered to be already, and it gets 'absorbed'. Local call method, called automatically.

**remove\_stop\_notifier(func)**

Remove the stop notifier from this controller.

Return `True` if the notifier was in this thread and is now removed, and `False` otherwise. Local call method.

**request\_stop()**

Request thread stop (send a stop command).

External call method.

**running()**

Check if the thread is running

**send\_interrupt(tag, value, priority=0)**

Send an interrupt message to the thread with a given tag, value and priority.

External call method.

**send\_message(tag, value, priority=0)**

Send a message to the thread with a given tag, value and priority.

External call method.

**send\_multicast(dst='any', tag=None, value=None, src=None, filter\_results=True)**

Send a multicast to the multicast pool.

By default, the multicast source is the thread's name. Return result synchronizers for all executed subscribed methods. Local call method.

**Parameters**

- **dst** (*str*) – multicast destination; can be a name, "all" (will pass all subscribers' destination filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" destination).
- **tag** (*str*) – multicast tag.
- **value** – multicast value.

- **src** (*str*) – multicast source; can be `None` (current thread name), a specific name, "all" (will pass all subscribers' source filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" source).
- **filter\_results** – if `True`, filter the results to exclude dummy synchronizers, which correspond to calls which do not return anything

**send\_multicast\_sync**(*dst='any', tag=None, value=None, src=None, timeout=None, default\_result=None, pass\_exception=True*)

Send a multicast to the multicast pool and synchronize the results, if available.

By default, the multicast source is the thread's name. Results are collected and synchronized only from the subscriptions which return them (i.e., set `return_result=True`). Local call method.

#### Parameters

- **dst** (*str*) – multicast destination; can be a name, "all" (will pass all subscribers' destination filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" destination).
- **tag** (*str*) – multicast tag.
- **value** – multicast value.
- **src** (*str*) – multicast source; can be `None` (current thread name), a specific name, "all" (will pass all subscribers' source filters), or "any" (will only be passed to subscribers specifically subscribed to multicast with "any" source).
- **timeout** – synchronization timeout (`None` means waiting forever)
- **default\_result** – default result value if synchronization failed (timed out, thread stopped, etc.)
- **pass\_exception** – if `True` and the signal processor raised an exception, raise it in this thread as well. If `pass_exception==True` and the returned value represents exception, re-raise it in the caller thread; otherwise, return *default*.

**send\_sync**(*tag, uid*)

Send a synchronization signal with the given tag and UID.

This method is rarely invoked directly, and is usually used by synchronizers code (e.g., [\*QThreadNotifier\*](#)). External call method.

**set\_func\_variable**(*name, func, use\_lock=True*)

Set a 'function' variable.

Acts as a thread variable to the external user, but instead of reading a stored value, it executed a function instead. Note, that the function is executed in the caller thread (i.e., the thread which tries to access the variable), so use of synchronization methods (commands, signals, locks) is highly advised.

If `use_lock==True`, then the function call will be wrapped into the usual variable lock, i.e., it won't run concurrently with other variable access. Local call method.

**set\_variable**(*name, value, update=False, notify=False, notify\_tag='changed/\*', simple=False*)

Set thread variable.

Can be called in any thread (controlled or external). If `notify==True`, send an multicast with the given *notify\_tag* (where "\*" symbol is replaced by the variable name). If `update==True` and the value is a dictionary, update the branch rather than overwrite it. If `simple==True`, assume that the result is a single atomic variable, in which case the lock is not used; note that in this case the threads waiting on this variable (or branches containing it) will not be notified. Local call method.

**sleep**(*timeout*, *wake\_on\_message=False*, *top\_loop=False*)

Sleep for a given time (in seconds).

Unlike `time.sleep()`, constantly checks the event loop for new messages (e.g., if stop or interrupt commands are issued). In addition, if `wake_on_message==True`, wake up if any message has been received; in this case, return `True` if the wait has been completed, and `False` if it has been interrupted by a message. If `top_loop==True`, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). If `timeout` is `None`, wait forever (usually, until the application is closed, or some interrupt message raises an error). Local call method.

**start**()

Start the thread.

External call method.

**started** = <Mock name='mock.QtCore.pyqtSignal()' id='140527858977616'>

This signal is emitted after the thread has started (after the setup code has been executed, before its lifetime state is changed)

**stop**(*code=0*, *sync=False*)

Stop the thread.

If called from the thread, stop immediately by raising a `threadprop.InterruptExceptionStop` exception. Otherwise, schedule thread stop. If the thread kind is "main", stop the whole application with the given exit code. Otherwise, stop the thread. If `sync==True` and the thread is not main or current, wait until it is completely stopped. Universal call method.

**subscribe\_direct**(*callback*, *srcs='any'*, *tags=None*, *dsts='any'*, *filt=None*, *subscription\_priority=0*, *scheduler=None*, *return\_result=False*, *sid=None*)

Subscribe asynchronous callback to a multicast.

If a multicast is sent, *callback* is called from the sending thread (not subscribed thread). Therefore, should be used with care. In Qt, analogous to making a signal connection with a direct call. By default, the subscribed destination is the thread's name. Local call method.

### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or [*str*]) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).
- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **subscription\_priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **scheduler** – if defined, multicast call gets scheduled using this scheduler instead of being called directly (which is the default behavior)

- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique id and return it).

**subscribe\_sync**(*callback*, *srcs*='any', *tags*=None, *dsts*='any', *filt*=None, *subscription\_priority*=0, *limit\_queue*=None, *call\_interrupt*=True, *add\_call\_info*=False, *return\_result*=False, *sid*=None)

Subscribe a synchronous callback to a multicast.

If a multicast is sent, *callback* is called from the *dest\_controller* thread (by default, thread which is calling this function) via the thread call mechanism (*QThreadController.call\_in\_thread\_callback()*). In Qt, analogous to making a signal connection with a queued call. By default, the subscribed destination is the thread's name. Local call method.

#### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or [*str*]) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).
- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **subscription\_priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **limit\_queue** (*int*) – limits the maximal number of scheduled calls (if the multicast is sent while at least *limit\_queue* callbacks are already in queue to be executed, ignore it) 0 or negative value means no limit (not recommended, as it can increase the queue indefinitely if the multicast rate is high enough)
- **call\_interrupt** – whether the call is an interrupt (call inside any loop, e.g., during waiting or sleeping), or it should be called in the main event loop
- **add\_call\_info** (*bool*) – if True, add a fourth argument containing a call information (tuple with a single element, a timestamps of the call).
- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique name).

**sync\_exec\_point**(*point*, *timeout*=None, *counter*=1)

Wait for the given execution point.

Automatically invoked points include "start" (thread starting), "run" (thread setup and ready to run), "cleanup" (thread stopping is invoked, starting to clean up) and "stop" (thread finished). If *timeout* is passed, raise *threadprop.TimeoutThreadError*. *counter* specifies the minimal number of prerequisite *notify\_exec\_point()* calls to finish the waiting (by default, a single call is enough). Return actual number of notifier calls up to date. External call method.

**sync\_stop()**

Wait until the controller and the thread are stopped.

External call method.

**sync\_variable(name, pred, timeout=None)**

Wait until thread variable with the given *name* satisfies the condition given by *pred*.

*pred* can be a variable values, a container (list, set, tuple) of possible values, or a function which takes one argument (variable value) and returns whether the condition is satisfied. It is executed in the caller thread.

External call method.

**unsubscribe(sid)**

Unsubscribe from a subscription with a given ID.

Note that multicasts which are already emitted but not processed will remain in the queue; if they need to be ignored, it should be handled explicitly. Local call method.

**wait\_for\_any\_message(timeout=None, top\_loop=False)**

Wait for any message (including synchronization messages or pokes).

If timeout is passed, raise `threadprop.TimeoutThreadError`. If `top_loop==True`, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**wait\_for\_message(tag, timeout=None, top\_loop=False)**

Wait for a single message with a given tag.

Return value of a received message with this tag. If timeout is passed, raise `threadprop.TimeoutThreadError`. If `top_loop==True`, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). Local call method.

**wait\_for\_sync(tag, uid, timeout=None)**

Wait for synchronization signal with the given tag and UID.

This method is rarely invoked directly, and is usually used by synchronizers code. If timeout is passed, raise `threadprop.TimeoutThreadError`. Local call method.

**wait\_until(check, timeout=None, top\_loop=False)**

Wait until a given condition is true.

Condition is given by the *check* function, which is called after every new received message and should return `True` if the condition is met. If `top_loop==True`, treat the waiting as the top message loop (i.e., any top loop message or signal can be executed here). If timeout is passed, raise `threadprop.TimeoutThreadError`. Local call method.

`pylablib.core.thread.controller.get_controller(name=None, sync=True, timeout=None, sync_point=None)`

Find a controller with a given name.

If *name* is not supplied, yield current controller instead. If *name* is of `int` type, interpret it as a thread id. If the controller is not present and `sync==True`, wait (with the given timeout) until the controller is running; otherwise, raise error if the controller is not running. If *sync\_point* is not `None`, synchronize to the thread *sync\_point* point (by default, "run", i.e., after the setup is done) before returning.

`pylablib.core.thread.controller.sync_controller(name, sync_point='run', timeout=None)`

Find a controller with a given name and synchronize to the given point.

If the controller is not present and `sync==True`, wait (with the given timeout) until the controller is running; otherwise, raise error if the controller is not running. Analogous to `get_controller(name, sync=True, timeout=timeout, sync_point=sync_point)`.



`pylablib.core.thread.controller.get_gui_controller(sync=False, timeout=None, create_if_missing=True)`

Get GUI thread controller.

If the controller is not present and `sync==True`, wait (with the given timeout) until the controller is running. If the controller is still not present and `create_if_missing==True`, initialize the standard GUI controller.

`pylablib.core.thread.controller.stop_controller(name=None, code=0, sync=True, require_controller=False)`

Stop a controller with a given name (current controller by default).

`code` specifies controller exit code (only applies to the main thread controller). If `require_controller==True` and the controller is not present, raise an error; otherwise, do nothing. If `sync==True`, wait until the controller is stopped.

`pylablib.core.thread.controller.stop_all_controllers(sync=True, concurrent=True, stop_self=True)`

Stop all running threads.

If `sync==True`, wait until all of the controllers are stopped. If `sync==True` and `concurrent==True` stop threads in concurrent manner (first issue stop messages to all of them, then wait until all are stopped). If `sync==True` and `concurrent==False` stop threads in consecutive manner (wait for each thread to stop before stopping the next one). If `stop_self==True` stop current thread after stopping all other threads.

`pylablib.core.thread.controller.stop_app(code=0, sync=False)`

Initialize stopping the application.

Do this either by stopping the GUI controller (if it exists), or by stopping all controllers. If `sync` is `True` and the thread is not the main one, wait at this point until the process is stopped during the app shutdown; otherwise, the execution will continue as normal, and the thread will be stopped at a later time during the app shutdown.

`pylablib.core.thread.controller.restart_app(code=0, sync=False)`

Restart the application.

Equivalent to `stop_app()` followed by the script restart. If `sync` is `True` and the thread is not the main one, wait at this point until the process is stopped during the app shutdown; otherwise, the execution will continue as normal, and the thread will be stopped at a later time during the app shutdown.

## pylablib.core.thread.multicast\_pool module

`class pylablib.core.thread.multicast_pool.TMulticast(src, tag, value)`

Bases: `tuple`

**src**

**tag**

**value**

`class pylablib.core.thread.multicast_pool.MulticastPool`

Bases: `object`

Multicast dispatcher (somewhat similar in functionality to Qt signals).

Manages dispatching multicasts between sources and destinations (callback functions). Each multicast has defined source, destination (both can also be "all" or "any", see methods descriptions for details), tag and value. Any thread can send a multicast or subscribe for a multicast with given filters (source, destination, tag, additional filters). If a multicast is emitted, it is checked against filters for all subscribers, and the passing ones are then called.



**subscribe\_direct**(*callback*, *srcs*='any', *dsts*='any', *tags*=None, *filt*=None, *priority*=0, *scheduler*=None, *return\_result*=False, *sid*=None)

Subscribe an asynchronous callback to a multicast.

If a multicast is sent, *callback* is called from the sending thread (not subscribed thread). Therefore, should be used with care. In Qt, analogous to making a signal connection with a direct call.

#### Parameters

- **callback** – callback function, which takes 3 arguments: source, tag, and value.
- **srcs** (*str* or [*str*]) – multicast source name or list of source names to filter the subscription; can be "any" (any source) or "all" (only multicasts specifically having "all" as a source).
- **dsts** (*str* or [*str*]) – multicast destination name or list of destination names to filter the subscription; can be "any" (any destination) or "all" (only source specifically having "all" as a destination).
- **tags** – multicast tag or list of tags to filter the subscription (any tag by default); can also contain Unix shell style pattern ("\*" matches everything, "?" matches one symbol, etc.)
- **filt** (*callable*) – additional filter function which takes 4 arguments: source, destination, tag, and value, and checks whether multicast passes the requirements.
- **priority** (*int*) – subscription priority (higher priority subscribers are called first).
- **scheduler** – if defined, multicast call gets scheduled using this scheduler instead of being called directly (which is the default behavior)
- **return\_result** – if True, use a result synchronizer to return the result of the subscribed call; otherwise, ignore the result
- **sid** (*int*) – subscription ID (by default, generate a new unique name).

#### Returns

subscription ID, which can be used to unsubscribe later.

**unsubscribe**(*sid*)

Unsubscribe from a subscription with a given ID

**send**(*src*, *dst*='any', *tag*=None, *value*=None)

Send a multicast.

#### Parameters

- **src** (*str*) – multicast source; can be a name, "all" (will pass all subscribers' source filters), or "any" (will only be passed to subscribers specifically subscribed to multicasts with "any" source).
- **dst** (*str*) – multicast destination; can be a name, "all" (will pass all subscribers' destination filters), or "any" (will only be passed to subscribers specifically subscribed to multicasts with "any" destination).
- **tag** (*str*) – multicast tag.
- **value** – multicast value.

## pylablib.core.thread.notifier module

**class** pylablib.core.thread.notifier.**ISkippableNotifier**(*skippable=False*)

Bases: `object`

Generic skippable notifier.

The main methods are `wait()` (wait until the event happened) and `notify()` (notify that the event happened). Only calls underlying waiting and notifying methods once, duplicate calls are ignored.

### Parameters

**skippable** (*bool*) – if `True`, allows for skippable wait events (if `notify()` is called before `wait()`, neither methods are actually called).

**wait**(\*args, \*\*kwargs)

Wait for the notification.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called after `notify()`, return immediately.

**notify**(\*args, \*\*kwargs)

Notify the waiting process.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called before `wait()`, return immediately.

**waiting**()

Check if waiting is in progress

**done\_wait**()

Check if waiting is done

**success\_wait**()

Check if waiting is done successfully

**done\_notify**()

Check if notifying is done

**waiting\_state**()

**notifying\_state**()

## pylablib.core.thread.profile module

pylablib.core.thread.profile.**start**(*reset=True*)

Start yappi profile logging.

If `reset==True`, reset the stats.

pylablib.core.thread.profile.**reset**()

Reset yappi profiling stats

pylablib.core.thread.profile.**stop**()

Stop yappi profiling

`pylablib.core.thread.profile.get_stats()`

Get yappi profiling stats.

Return tuple `((ttime,wtime), (threads,ctls))`. Here `ttime` and `wtime` are total execution time (sum of all thread times) and the wall time (since the last reset) respectively. `threads` are yappi-generated stats, and `ctls` is the list `[(name,ctl)]` with the controller names and thread controllers, which are ordered in the same way as `threads` (for any non-controlled or stopped thread these are set to `None`).

`pylablib.core.thread.profile.print_stats(nfunc=None, ntotfunc=None, min_func_frac=0.001)`

Print yappi profiling stats.

`nfunc` is the number of top (most expensive) functions to print per each thread, `ntotfunc` is the number of global top function to print; `None` for either means that they are not printed. `min_func_frac` specifies the minimal fraction of the total time for which the function stats are still printed (to prevent lost of printouts for “cheap” threads).

## pylablib.core.thread.synchronizing module

**class** `pylablib.core.thread.synchronizing.QThreadNotifier`(*skippable=True*)

Bases: `ISkippableNotifier`

Wait-notify thread synchronizer for controlled Qt threads based on `notifier.ISkippableNotifier`.

Like `notifier.ISkippableNotifier`, the main functions are `ISkippableNotifier.wait()` (wait in a message loop until notified or until timeout expires) and `ISkippableNotifier.notify()` (notify the waiting thread). Both of these can only be called once and will raise an error on repeating calls. Along with notifying a variable can be passed, which can be accessed using `get_value()` and `get_value_sync()`.

### Parameters

**skippable** (*bool*) – if `True`, allows for skippable wait events (if `ISkippableNotifier.notify()` is called before `ISkippableNotifier.wait()`, neither methods are actually called).

**get\_value()**

Get the value passed by the notifier (doesn’t check if it has been passed already)

**get\_value\_sync**(*timeout=None*)

Wait (with the given *timeout*) for the value passed by the notifier

**done\_notify()**

Check if notifying is done

**done\_wait()**

Check if waiting is done

**notify**(\*args, \*\*kwargs)

Notify the waiting process.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called before `wait()`, return immediately.

**notifying\_state()**

**success\_wait()**

Check if waiting is done successfully

**wait(\*args, \*\*kwargs)**

Wait for the notification.

Can only be called once per notifier lifetime. If the notifier allows skipping, and this method is called after *notify()*, return immediately.

**waiting()**

Check if waiting is in progress

**waiting\_state()**

**class** pylablib.core.thread.synchronizing.QMultiThreadNotifier

Bases: *object*

Wait-notify thread synchronizer that can be used for multiple threads and called multiple times.

Performs similar function to conditional variables. The synchronizer has an internal counter which is increased by 1 every time it is notified. The wait functions have an option to wait until the counter reaches the specific counter value (usually, 1 above the last wait call).

**wait(state=1, timeout=None)**

Wait until notifier counter is equal to at least *state*

Return current counter state plus 1, which is the next smallest value resulting in waiting.

**wait\_until(condition, timeout=None)**

Wait until *condition* is met.

*condition* is a function which is called (in the waiting thread) every time the synchronizer is notified. If it return non-False, the waiting is complete and its result is returned.

**notify()**

Notify all waiting threads

**fail()**

Mark notifier as fails

Fails all waiting notifiers. All subsequent wait calls raise an error

**class** pylablib.core.thread.synchronizing.QLockNotifier

Bases: *object*

Resource lock.

Behaves similarly to the regular lock, but waiting is done in the message loop, which still allows interrupts.

**acquire(timeout=None)**

**release()**

## pylablib.core.thread.threadprop module

**exception** pylablib.core.thread.threadprop.ThreadError(*msg=None*)

Bases: *RuntimeError*

Generic thread error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.core.thread.threadprop.NoControllerThreadError(msg=None)

Bases: [ThreadError](#)

Thread error for a case of thread having no controllers

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.core.thread.threadprop.DuplicateControllerThreadError(msg=None)

Bases: [ThreadError](#)

Thread error for a case of a duplicate thread controller

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.core.thread.threadprop.TimeoutThreadError(msg=None)

Bases: [ThreadError](#), [TimeoutError](#)

Thread error for a case of a wait timeout

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**characters\_written**

**errno**

POSIX exception code

**filename**

exception filename

**filename2**

second exception filename

**strerror**

exception strerror

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.thread.threadprop.NoMessageThreadError(msg=None)`

Bases: [`ThreadError`](#)

Thread error for a case of trying to get a non-existing message

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.thread.threadprop.SkippedCallError(msg=None)`

Bases: [`ThreadError`](#)

Thread error for a case of external call getting skipped (unscheduled)

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.thread.threadprop.InterruptException(msg=None)`

Bases: [`Exception`](#)

Generic interrupt exception (raised by some function to signal interrupts from other threads)

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.thread.threadprop.InterruptExceptionStop(msg=None)`

Bases: [`InterruptException`](#)

Interrupt exception denoting thread stop request

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

`pylablib.core.thread.threadprop.get_app()`

Get current application instance

`pylablib.core.thread.threadprop.get_gui_thread()`

Get main (GUI) thread, or None if application is not running

`pylablib.core.thread.threadprop.is_gui_running()`

Check if GUI is running

`pylablib.core.thread.threadprop.is_gui_thread()`

Check if the current thread is the one running the GUI loop

`pylablib.core.thread.threadprop.current_controller(require_controller=True)`

Get controller of the current thread.

If the current thread has not controller *and* `require_controller==True`, raise an error; otherwise, return None.

## pylablib.core.thread.utils module

**class** `pylablib.core.thread.utils.ReadChangeLock`

Bases: `object`

Lock based on condition variables which handles a state which can be read or changed.

Any number of threads can read simultaneously, but changing is incompatible with other reading or changing.

**can\_read()**

Check if the state can be read

**can\_change()**

Check if the state can be changed

**reading()**

Context manager denoting reading event

**changing()**

Context manager denoting changing event

## Module contents

### pylablib.core.utils package

#### Submodules

### pylablib.core.utils.array\_utils module

`pylablib.core.utils.array_utils.as_array(data, force_copy=False, try_object=True)`

Turn *data* into a numpy array.

If `force_copy==True`, copy the data if it's already a numpy array. If `try_object==False`, only try to convert to numerical numpy arrays; otherwise, generic numpy arrays (with `dtype=="object"`) are acceptable.

`pylablib.core.utils.array_utils.get_shape(data, strict=False)`

Get the data shape.

If the data is a nested list and `strict==True`, raise an error unless all sublists have the same length (i.e., the data is rectangular).

### pylablib.core.utils.cext\_tools module

`pylablib.core.utils.cext_tools.try_import_cext()`

Context manager for trying to import a possibly missing C extension; if an error arises, re-raises with a more detailed message

### pylablib.core.utils.crc module

`pylablib.core.utils.crc.binv(a, l)`

Reverse bit order of *a* treating it as an *l*-bit number

`pylablib.core.utils.crc.calc_table(poly, ref=False)`

Calculate CRC byte table for the given polynomial and reflection parameter.

*ref* specifies whether both input and output bit sequences are reflected.

`pylablib.core.utils.crc.crc(msg, poly, refin=False, refout=False, init=0, xorout=0)`

Calculate CRC for the given message, polynomial, and additional parameters.

*msg* should be a bytes object, while *poly* is an integer with the polynomial coefficients.

### pylablib.core.utils.ctypes\_wrap module

`pylablib.core.utils.ctypes_wrap.get_value(rval)`

Get value of a ctypes variable

`pylablib.core.utils.ctypes_wrap.setup_func(func, argtypes, restype=None, errcheck=None)`

Setup a ctypes function.

Assign *argtypes* (list of argument types), *restype* (return value type) and *errcheck* (error checking function called for the return value).

**class** `pylablib.core.utils.ctypes_wrap.CFunctionWrapper`(*restype=None, errcheck=None, tuple\_single\_retval=False, return\_res='auto', default\_rvals='rest', pointer\_byref=False*)

Bases: `object`

Wrapper object for ctypes function.

The main methods are `wrap_annotated()` and `wrap_bare()`, which wrap a ctypes function and returns a Python function with a proper signature. These methods can also handle some standard use cases such as passing parameters by reference, or setting up the function arguments, or parsing the results. These methods can also be invoked when the wrapper is used as a callable; in this case, the exact method is determined by the presence of `.argtypes` attribute in the supplied function.

#### Parameters

- **restype** – default type of the function return value when calling `wrap_bare()` and *restype* is not supplied there explicitly (defaults to `ctypes.int`)
- **errcheck** – default error-checking function which is automatically called for the return value; can also be overridden explicitly when calling wrapping methods if `None`, no error checking method
- **tuple\_single\_retval** (*bool*) – determines if a single return values gets turned into a single-element tuple



- **return\_res** (*bool*) – determined if the function result gets returned; only used when list of return arguments (*rvals*) to wrapping functions is not explicitly supplied; can also be set to "auto" (default), which means that function returns its return value when no other *rvals* are found, and omits it otherwise.
- **default\_rvals** – default value for *rvals* in *wrap\_annotated()* and *wrap\_bare()*, if it is specified as *None* (default for those methods).
- **pointer\_byref** (*bool*) – if *True*, use explicit pointer creation instead of *byref* (in rare cases use of *byref* crashes the call).

**byref**(*value*)

**wrap\_bare**(*func*, *argtypes*, *argnames=None*, *restype=None*, *args='nonrval'*, *rvals='default'*, *argprep=None*, *rconv=None*, *byref='all'*, *errcheck=None*)

Annotate and wrap bare C function in a Python call.

Same as *wrap\_annotated()*, but annotates the function first.

#### Parameters

- **func** – C function
- **argtypes** – list of ctypes types corresponding to function arguments; gets assigned as *func.argtypes*
- **argnames** – list of argument names; if not supplied, generated automatically as "arg1", "arg2", etc. Same for names which are defined as *None*.
- **restype** – type of the function return value; if *None*, use the value supplied to the wrapper constructor (defaults to *ctypes.int*)
- **args** – names of Python function arguments; can also be "all" (all C function arguments in that order), or "nonrval" (same, but with return value arguments excluded) by default, use "nonrval"
- **rvals** – names of return value arguments; can include either a C function argument name, or *None* (which means the function return value); can also be "rest" (lists all the arguments not included into *args*; if *args=="nonrval"*, assume that there are no *rvals*), "pointer" (assume that all pointer arguments are *rvals*; this does not include *c\_void\_p*, *c\_char\_p*, or *c\_wchar\_p*); by default, use the value supplied on the wrapper creation ("rest" by default)
- **argprep** – dictionary {*name*: *prep*} of ways to prepare of C function arguments; each *prep* can be a value (which is assumed to be default argument value), or a callable, which is given values of Python function arguments
- **rconv** – dictionary {*name*: *conv*} of converters of the return values; each *conv* is a function which takes 3 arguments: unconverted ctypes value, dictionary of all C function arguments, and dictionary of all Python function arguments if *conv* takes less than 3 argument, then the arguments list is trimmed (e.g., if it takes only one argument, it will be an unconverted value) *conv* can also be "ctypes" (return raw ctypes value), or "raw" (return raw value for buffers).
- **byref** – list of all argument names which should be passed by reference; by default, it includes all arguments listed in *rvals*
- **errcheck** – error-checking function which is automatically called for the return value; if *None*, use the value supplied to the wrapper constructor (none by default)

**wrap\_annotated**(*func*, *args*='nonrval', *rvals*='default', *alias*=None, *argprep*=None, *rconv*=None, *byref*='all', *errcheck*=None)

Wrap annotated C function in a Python call.

Assumes that the functions has defined `.argtypes` (list of argument types) and `.argnames` (list of argument names) attributes.

#### Parameters

- **func** – C function
- **args** – names of Python function arguments; can also be "all" (all C function arguments in that order), or "nonrval" (same, but with return value arguments excluded); by default, use "nonrval"
- **rvals** – names of return value arguments; can include either a C function argument name, or None (which means the function return value); can also be "rest" (lists all the arguments not included into args; if `args=="nonrval"`, assume that there are no rvals), "pointer" (assume that all pointer arguments are rvals; this does not include `c_void_p`, `c_char_p`, or `c_wchar_p`); by default, use the value supplied on the wrapper creation ("rest" by default)
- **alias** – either a list of argument names which replace `.argnames`, or a dictionary {`argname`: `alias`} which transforms names; all names in all other parameters (`rvals`, `argprep`, `rconv`, and `byref`) take aliased names
- **argprep** – dictionary {`name`: `prep`} of ways to prepare of C function arguments; each `prep` can be a value (which is assumed to be default argument value), or a callable, which is given values of Python function arguments
- **rconv** – dictionary {`name`: `conv`} of converters of the return values; each `conv` is a function which takes 3 arguments: unconverted ctypes value, dictionary of all C function arguments, and dictionary of all Python function arguments if `conv` takes less than 3 argument, then the arguments list is trimmed (e.g., if it takes only one argument, it will be an unconverted value)
- **byref** – list of all argument names which should be passed by reference; by default, it includes all arguments listed in `rvals`
- **errcheck** – error-checking function which is automatically called for the return value; if None, use the value supplied to the wrapper constructor (none by default)

`pylablib.core.utils.ctypes_wrap.strprep`(*l*, *ctype*=None, *unicode*=False)

Make a string preparation function.

Return a function which creates a string with a fixed length of *l* bytes and returns a pointer to it. *ctype* can specify the type of the result (by default, `ctypes.c_char_p`).

`pylablib.core.utils.ctypes_wrap.strconv`(*l*=None, *unicode*=False)

Make a string conversion function.

Return a function which converts a pointer a string. If `unicode==True`, use regular single-byte string conversion; otherwise, use unicode (`wchar`) string conversion; if specified, *l* determines the string length (otherwise use the standard null-terminated string convention).

`pylablib.core.utils.ctypes_wrap.buffprep`(*size\_arg\_pos*, *dtype*)

Make a buffer preparation function.

Return a function which creates a string with a variable size (specified by an argument at a position *size\_arg\_pos*). The buffer size is given in elements. *dtype* specifies the datatype of the buffer, whose size is used to determine buffer size in bytes.

`pylablib.core.utils.ctypes_wrap.buffconv(size_arg_pos, dtype)`

Make a buffer conversion function.

Return a function which converts a pointer of a variable size (specified by an argument at a position *size\_arg\_pos*) into a numpy array. The buffer size is given in elements. *dtype* specifies the datatype of the resulting array.

**class** `pylablib.core.utils.ctypes_wrap.CStructWrapper(struct=None)`

Bases: `object`

Wrapper around a ctypes structure, which allows for easier creation of parsing of these structures.

When created, all structure fields can be accessed/modified as attributes of the wrapper object. It can also be converted into tuple using `tup()` method, or back into C structure using `to_struct()` method.

Class variable `_struct` should be set to the ctypes structure which is being wrapped. Several other class variables determine the behavior when generating and parsing:

- `_prep`: dictionary {*name*: *prep*} of methods to prepare individual structure parameters; can be either a value or a function (which takes as ordered arguments all structure fields as ctypes values)
- `_conv`: dictionary {*name*: *conv*} of methods to convert individual structure parameters when parsing a C structure; can be either a function (which takes ctypes value of the field as a single argument) or a value; also can be used as a source of default values on wrapper creation
- `_tup`: dictionary {*name*: *conv*} of functions to convert structure values when generating a tuple
- `_tup_exc`: list of values to exclude from the resulting tuple
- `_tup_inc`: list of values to include in the resulting tuple (if `None`, include all)
- `_tup_add`: list of values to add to the resulting tuple (these values must then exist either as attributes, or as entries in `_tup` dictionary)
- `_tup_order`: order of fields in the returned tuple (by default, same as structure order)

Also specifies two overloaded methods for a more flexible preparation/conversion of structures. `conv()` takes no arguments and is called in the end of wrapper creation to finish setting up attributes. `prep()` takes a single argument (C structure) and is called when converting into a C structure to finish setting up the fields (e.g., size field).

#### Parameters

**struct** – C structure to wrap (if `None`, create a new ‘blank’ structure).

**to\_struct()**

Convert wrapper into a C structure

**prep(struct)**

Prepare C structure after creation (by default, do nothing)

**conv()**

Prepare wrapper after setting up the fields from the wrapped structure

**tup()**

Convert wrapper into a named tuple

**classmethod prep\_struct(\*args, \*\*kwargs)**

Prepare a blank C structure

**classmethod prep\_struct\_args(\*args, \*\*kwargs)**

Prepare a C structure with the given supplied fields

**classmethod** `tup_struct(struct, *args, **kwargs)`

Convert C structure into a named tuple

`pylablib.core.utils.ctypes_wrap.class_tuple_to_dict(val, norm_strings=True, expand_lists=False)`

Convert a named tuple (usually, a tuple returned by `CStructWrapper.tup()`) into a dictionary.

Iterate recursively over all named tuple elements as well. If `norm_strings==True`, automatically translate byte strings into regular ones. If `expand_lists==True`, iterate recursively over lists members.

## pylablib.core.utils.dictionary module

Tree-like multi-level dictionary with advanced indexing options.

`pylablib.core.utils.dictionary.split_path(path, omit_empty=True, sep=None)`

Split generic path into individual path entries.

### Parameters

- **path** – Generic path. Lists and tuples (possible nested) are flattened; strings are split according to separators; non-strings are converted into strings first.
- **omit\_empty** (*bool*) – Determines if empty entries are skipped.
- **sep** (*str*) – If not `None`, defines regex for path separators; default separator is `'/'`.

### Returns

A list of individual entries.

### Return type

`list`

`pylablib.core.utils.dictionary.normalize_path_entry(entry, case_normalization=None)`

Normalize the case of the entry if it's not case-sensitive. Normalization is either `None` (no normalization, names are case-sensitive), `'lower'` or `'upper'`

`pylablib.core.utils.dictionary.normalize_path(path, omit_empty=True, case_normalization=None, sep=None, force=False)`

Split and normalize generic path into individual path entries.

### Parameters

- **path** – Generic path. Lists and tuples (possible nested) are flattened; strings are split according to separators; non-strings are converted into strings first.
- **omit\_empty** (*bool*) – Determines if empty entries are skipped.
- **case\_normalization** (*str*) – Case normalization rules; can be `None` (no normalization, names are case-sensitive), `'lower'` or `'upper'`.
- **sep** (*str*) – If not `None`, defines regex for path separators; default separator is `'/'`.
- **force** (*bool*) – If `False`, treat lists as if they're already normalized.

### Returns

A list of individual normalized entries.

### Return type

`list`

`pylablib.core.utils.dictionary.is_dictionary(obj, generic=False)`

Determine if the object is a dictionary.

#### Parameters

- **obj** – object
- **generic** (*bool*) – if False, passes only *Dictionary* (or subclasses) objects; otherwise, passes any dictionary-like object.

#### Returns

bool

`pylablib.core.utils.dictionary.as_dictionary(obj, case_normalization=None)`

Convert object into *Dictionary* with the given parameters.

If object is already a *Dictionary* (or its subclass), return unchanged, even if its parameters are different.

`pylablib.core.utils.dictionary.as_dict(obj, style='nested', copy=True)`

Convert object into standard *dict* with the given parameters.

If object is already a *dict*, return unchanged, even if the parameters are different.

**class** `pylablib.core.utils.dictionary.Dictionary(root=None, case_normalization=None, copy=True)`

Bases: *object*

Multi-level dictionary.

Access is done by path (all path elements are converted into strings and concatenated to form a single string path). If dictionary is not case-sensitive, all inserted and accessed paths are normalized to lower or upper case.

#### Parameters

- **root** (*dict* or *Dictionary*) – Initial value.
- **case\_normalization** (*str*) – Case normalization rules; can be None (no normalization, names are case-sensitive), 'lower' or 'upper'.
- **copy** (*bool*) – If True, make copy of the supplied data; otherwise, just make it the root.

**Warning:** If `copy==False`, the root data is already assumed to be normalized. If it isn't, the behavior might be incorrect.

**static** `is_dictionary(obj, generic=True)`

Determine if the object is a dictionary.

#### Parameters

- **obj**
- **generic** (*bool*) – if False, passes only *Dictionary* (or subclasses) objects; otherwise, passes any dictionary-like object.

#### Returns

bool

**static** `as_dictionary(obj, case_normalization=None)`

Convert object into *Dictionary* with the given parameters.

If object is already a *Dictionary* (or its subclass), return unchanged, even if its parameters are different.

**add\_entry**(*path*, *value*, *force=False*, *branch\_option='normalize'*)

Add value to a given path (overwrite leaf value if necessary).

Doesn't replace leaves with branches and vice-versa if *force==False*.

**Parameters**

- **path**
- **value**
- **force** (*bool*) – If True, change leaf into a branch and vice-versa; otherwise, raises *ValueError* if the conversion is necessary.
- **branch\_option** (*str*) –

Decides what to do if the value is dictionary-like:

- 'attach' – just attach the root,
- 'copy' – copy and attach,
- 'normalize' – copy while normalizing all the keys according to the current rules.

**get\_entry**(*path*, *as\_pointer=False*)

Get entry at a given path

**Parameters**

- **path**
- **as\_pointer** (*bool*) – If True and entry is not a leaf, return *DictionaryPointer*; otherwise, return *Dictionary*

**has\_entry**(*path*, *kind='all'*)

Determine if the path is in the dictionary.

*kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'.

**is\_leaf\_path**(*path*)

Determine if the path is in the dictionary and points to a leaf

**is\_branch\_path**(*path*)

Determine if the path is in the dictionary and points to a branch

**get\_max\_prefix**(*path*, *kind='all'*)

Find the longest prefix of *path* contained in the dictionary.

Return tuple (*prefix*, *rest*), where both path entries are normalized according to the dictionary rules (i.e., these are lists representing normalized paths). *kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'. If the longest prefix is of a different kind, return (None, None).

**del\_entry**(*path*)

Delete entry from the dictionary.

Return True if the path was present. Note that it never raises *KeyError*.

**size**()

Return the total size of the dictionary (number of nodes)

**get**(*path*, *default=None*)

Analog of dict.get(): D.get(k,d) -> D[k] if k in D else d

**pop**(*path*, *default=None*)

Analog of `dict.pop()`: remove value at *path* and return it if *path* in *D*, otherwise return *default*

Note that it never raises `KeyError`.

**setdefault**(*path*, *default=None*)

Analog of `dict.setdefault()`: `D.setdefault(k,d) -> D.get(k,d)`, also sets `D[k]=d` if *k* not in *D*.

**items**(*ordered=False*, *leafs=False*, *path\_kind='split'*, *wrap\_branches=True*)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If `True`, loop over keys in alphabetic order.
- **leafs** (*bool*) – If `True`, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either `"split"` (each path is a tuple of individual keys), or `"joined"` (each path is a single string)
- **wrap\_branches** (*bool*) – if `True`, wrap sub-branches into `DictionaryPointer` objects; otherwise, return them as nested built-in dictionaries

**iteritems**(*ordered=False*, *leafs=False*, *path\_kind='split'*, *wrap\_branches=True*)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If `True`, loop over keys in alphabetic order.
- **leafs** (*bool*) – If `True`, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either `"split"` (each path is a tuple of individual keys), or `"joined"` (each path is a single string)
- **wrap\_branches** (*bool*) – if `True`, wrap sub-branches into `DictionaryPointer` objects; otherwise, return them as nested built-in dictionaries

**viewitems**(*ordered=False*, *leafs=False*, *path\_kind='split'*, *wrap\_branches=True*)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If `True`, loop over keys in alphabetic order.
- **leafs** (*bool*) – If `True`, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either `"split"` (each path is a tuple of individual keys), or `"joined"` (each path is a single string)
- **wrap\_branches** (*bool*) – if `True`, wrap sub-branches into `DictionaryPointer` objects; otherwise, return them as nested built-in dictionaries

**values**(*ordered=False*, *leafs=False*, *wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If `True`, loop over keys in alphabetic order.

- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**viewvalues**(*ordered=False, leafs=False, wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**itervalues**(*ordered=False, leafs=False, wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**keys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**viewkeys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**iterkeys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.



- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**paths**(*ordered=False, topdown=False, path\_kind='split'*)

Return list of all paths (leafs and nodes).

#### Parameters

- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **topdown** (*bool*) – If True, return node’s leafs before its subtrees leafs.
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**internodes**(*to\_visit='leafs', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

#### Parameters

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and [DictionaryPointer](#) for branches. If `include_path==True`, yields tuple (path, value), where *path* is in the form of a normalized list.

**nodes**(*to\_visit='leafs', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

#### Parameters

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and [DictionaryPointer](#) for branches. If `include_path==True`, yields tuple (path, value), where *path* is in the form of a normalized list.

**merge**(*source, path="", overwrite=True, normalize\_paths=True*)

Attach source ([dict](#) or other [Dictionary](#)) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to [add\\_entry\(\)](#), merges two branches instead of removing the old branch completely.

#### Parameters

- **source** (*dict* or [Dictionary](#))

- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**update**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Attach source (*dict* or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to `add_entry()`, merges two branches instead of removing the old branch completely.

#### Parameters

- **source** (*dict* or *Dictionary*)
- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**detach**(*path*)

Remove a branch or a leaf from the current dictionary.

Branch is returned as a separate *Dictionary*. If *path* is missing, raise a *KeyError*.

**collect**(*paths*, *detach*=False, *ignore\_missing*=True)

Collect a set of subpaths into a separate dictionary.

#### Parameters

- **paths** – list or set of paths
- **detach** – if True, added branches are removed from this dictionary
- **ignore\_missing** – if True, ignore paths from the list which are not present in this dictionary; otherwise, raise a *KeyError*.

**branch\_copy**(*branch*="")

Get a copy of the branch as a *Dictionary*

**copy**()

Get a full copy the dictionary

**updated**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Get a copy of the dictionary and attach a new branch to it.

Parameters are the same as in the *Dictionary.merge()*.

**as\_dict**(*style*='nested', *copy*=True)

Convert into a *dict* object.

#### Parameters

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,

- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**asdict**(style='nested', copy=True)

Convert into a [dict](#) object.

#### Parameters

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**as\_json**(style='nested')

Convert into a JSON string.

#### Parameters

**style** (*str*) – Determines style of the result: - 'nested' – subtrees are turned into nested dictionaries, - 'flat' – single dictionary is formed with full paths as keys.

**classmethod from\_json**(data, case\_normalization=None)

Convert JSON representations of a dictionary into a [Dictionary](#) object

**as\_pandas**(index\_key=True, as\_series=True)

Convert into a pandas DataFrame or Series object.

#### Parameters

- **index\_key** (*bool*) – If False, create a 2-column table with the first column ("key") containing string path and the second column ("value") containing value; otherwise, move key to the table index.
- **as\_series** (*bool*) – If index\_key==True and as\_series==True, convert the resulting DataFrame into 1D Series (the key is the index); otherwise, keep it as a single-column table

**get\_path**()

**branch\_pointer**(branch="")

Get a [DictionaryPointer](#) of a given branch

**map\_self**(func, to\_visit='leafs', pass\_path=False, topdown=False, branch\_option='normalize')

Apply *func* to the nodes in the dictionary.

Note that any pointers to the replaced branches or their sub-branches will become invalid.

#### Parameters

- **func** (*callable*) – Mapping function. Leafs are passed by value, branches (if visited) are passed as [DictionaryPointer](#).
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the map function.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *func*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

- **branch\_option** (*str*) – If the function returns a dict-like object, determines how to incorporate into the dictionary; can be "normalize" (make a copy with normalized paths and insert that), "copy" (make a copy without normalization), or "attach" (simply replace the value without copying and normalization)

**filter\_self**(*pred*, *to\_visit*='leafs', *pass\_path*=False, *topdown*=False)

Remove all the nodes from the dictionary for which *pred* returns False.

#### Parameters

- **pred** (*callable*) – Filter function. Leafs are passed to *pred* by value, branches (if visited) are passed as *DictionaryPointer*.
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the predicate.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *pred*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

**diff**(*other*)

Perform an element-wise comparison to another Dictionary.

If the other Dictionary has a different case sensitivity, raise *ValueError*.

#### Returns

*DictionaryDiff*

**static diff\_flatdict**(*first*, *second*)

Find the difference between flat *dict* objects.

#### Returns

*DictionaryDiff*

**static find\_intersection**(*dicts*, *use\_flatten*=False)

Find intersection of multiple dictionaries.

#### Parameters

- **dicts** (*[Dictionary]*)
- **use\_flatten** (*bool*) – If True flatten all dictionaries before comparison (works faster for a large number of dictionaries).

#### Returns

*DictionaryIntersection*

**get\_matching\_paths**(*pattern*, *wildkey*='\*', *wildpath*='\*\*', *only\_leaves*=True)

Get all paths in the tree that match the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If True, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, *only\_leaves*=False is analogous to adding *wildpath* at the end of the pattern.

**get\_matching\_subtree**(*pattern*, *wildkey*='\*', *wildpath*='\*\*', *only\_leaves*=True)

Get a subtree containing nodes with paths matching the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If True, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, *only\_leaves*=False is analogous to adding *wildpath* at the end of the pattern.

**class** pylablib.core.utils.dictionary.**DictionaryDiff**(*same*, *changed\_from*, *changed\_to*, *removed*, *added*)

Bases: *tuple*

Describes a difference between the two dictionaries.

#### **same**

Contains the leafs which is the same.

#### Type

*Dictionary*

#### **changed\_from**

Contains the leafs from the first dictionary which have different values in the second dictionary.

#### Type

*Dictionary*

#### **changed\_to**

Contains the leafs from the second dictionary which have different values in the first dictionary.

#### Type

*Dictionary*

#### **removed**

Contains the leafs from the first dictionary which are absent in the second dictionary.

#### Type

*Dictionary*

#### **added**

Contains the leafs from the second dictionary which are absent in the first dictionary.

#### Type

*Dictionary*

**class** pylablib.core.utils.dictionary.**DictionaryIntersection**(*common*, *individual*)

Bases: *tuple*

Describes the result of finding intersection of multiple dictionaries.

#### **common**

Contains the intersection of all dictionaries.

#### Type

*Dictionary*

**individual**

Contains list of difference from intersection for all dictionaries.

**Type**

[*Dictionary*]

```
class pylablib.core.utils.dictionary.DictionaryPointer(root=None, pointer=None,  
                                                    case_normalization=None, copy=True)
```

Bases: *Dictionary*

Similar to *Dictionary*, but can point at one of the branches instead of the full dictionary.

Effect is mostly equivalent to prepending some path to all queries.

**Parameters**

- **root** (*dict* or *Dictionary*) – Complete tree.
- **pointer** – Path to the pointer location.
- **case\_normalization** (*str*) – Case normalization rules; can be *None* (no normalization, names are case-sensitive), 'lower' or 'upper'.
- **copy** (*bool*) – If *True*, make copy of the supplied data; otherwise, just make it the root.

**Warning:** If *copy==False*, the root data is already assumed to be normalized. If it isn't, the behavior might be incorrect.

**get\_path()**

Return pointer path in the whole dictionary.

```
move_to(path="", absolute=True)
```

Move the pointer to a new path.

**Parameters**

- **path**
- **absolute** (*bool*) – If *True*, path is specified with respect to the root; otherwise, it's specified with respect to the current position (and can only go deeper).

```
move_up(levels, strict=True)
```

Move the pointer by the given number of levels up.

If *strict==True* and there are not enough levels above, raise an error. Otherwise, stop at the top dictionary level.

```
branch_pointer(branch="")
```

Get a *DictionaryPointer* of a given branch.

```
add_entry(path, value, force=False, branch_option='normalize')
```

Add value to a given path (overwrite leaf value if necessary).

Doesn't replace leaves with branches and vice-verse if *force==False*.

**Parameters**

- **path**
- **value**

- **force** (*bool*) – If True, change leaf into a branch and vice-versa; otherwise, raises `ValueError` if the conversion is necessary.
- **branch\_option** (*str*) –

Decides what to do if the value is dictionary-like:

- 'attach' – just attach the root,
- 'copy' – copy and attach,
- 'normalize' – copy while normalizing all the keys according to the current rules.

**as\_dict** (*style='nested', copy=True*)

Convert into a `dict` object.

#### Parameters

- **style** (*str*) –

Determines style of the result:

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and `style=='nested'`, return the root dictionary.

**static as\_dictionary** (*obj, case\_normalization=None*)

Convert object into `Dictionary` with the given parameters.

If object is already a `Dictionary` (or its subclass), return unchanged, even if its parameters are different.

**as\_json** (*style='nested'*)

Convert into a JSON string.

#### Parameters

**style** (*str*) – Determines style of the result: - 'nested' – subtrees are turned into nested dictionaries, - 'flat' – single dictionary is formed with full paths as keys.

**as\_pandas** (*index\_key=True, as\_series=True*)

Convert into a pandas DataFrame or Series object.

#### Parameters

- **index\_key** (*bool*) – If False, create a 2-column table with the first column ("key") containing string path and the second column ("value") containing value; otherwise, move key to the table index.
- **as\_series** (*bool*) – If `index_key==True` and `as_series==True`, convert the resulting DataFrame into 1D Series (the key is the index); otherwise, keep it as a single-column table

**asdict** (*style='nested', copy=True*)

Convert into a `dict` object.

#### Parameters

- **style** (*str*) –

Determines style of the result:

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**branch\_copy**(*branch=""*)

Get a copy of the branch as a *Dictionary*

**collect**(*paths*, *detach=False*, *ignore\_missing=True*)

Collect a set of subpaths into a separate dictionary.

#### Parameters

- **paths** – list or set of paths
- **detach** – if True, added branches are removed from this dictionary
- **ignore\_missing** – if True, ignore paths from the list which are not present in this dictionary; otherwise, raise a *KeyError*.

**copy**()

Get a full copy the dictionary

**del\_entry**(*path*)

Delete entry from the dictionary.

Return True if the path was present. Note that it never raises *KeyError*.

**detach**(*path*)

Remove a branch or a leaf from the current dictionary.

Branch is returned as a separate *Dictionary*. If *path* is missing, raise a *KeyError*.

**diff**(*other*)

Perform an element-wise comparison to another Dictionary.

If the other Dictionary has a different case sensitivity, raise *ValueError*.

#### Returns

*DictionaryDiff*

**static diff\_flatdict**(*first*, *second*)

Find the difference between flat *dict* objects.

#### Returns

*DictionaryDiff*

**filter\_self**(*pred*, *to\_visit='leafs'*, *pass\_path=False*, *topdown=False*)

Remove all the nodes from the dictionary for which *pred* returns False.

#### Parameters

- **pred** (*callable*) – Filter function. Leafs are passed to *pred* by value, branches (if visited) are passed as *DictionaryPointer*.
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the predicate.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *pred*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

**static find\_intersection**(*dicts*, *use\_flatten=False*)

Find intersection of multiple dictionaries.

#### Parameters



- **dicts** (*[Dictionary]*)
- **use\_flatten** (*bool*) – If True flatten all dictionaries before comparison (works faster for a large number of dictionaries).

**Returns***DictionaryIntersection***classmethod** **from\_json**(*data, case\_normalization=None*)Convert JSON representations of a dictionary into a *Dictionary* object**get**(*path, default=None*)

Analog of dict.get(): D.get(k,d) -&gt; D[k] if k in D else d

**get\_entry**(*path, as\_pointer=False*)

Get entry at a given path

**Parameters**

- **path**
- **as\_pointer** (*bool*) – If True and entry is not a leaf, return *DictionaryPointer*; otherwise, return *Dictionary*

**get\_matching\_paths**(*pattern, wildkey='\*', wildpath='\*\*', only\_leaves=True*)

Get all paths in the tree that match the provided pattern.

**Parameters**

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If True, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, **only\_leaves=False** is analogous to adding wildpath at the end of the pattern.

**get\_matching\_subtree**(*pattern, wildkey='\*', wildpath='\*\*', only\_leaves=True*)

Get a subtree containing nodes with paths matching the provided pattern.

**Parameters**

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If True, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, **only\_leaves=False** is analogous to adding wildpath at the end of the pattern.

**get\_max\_prefix**(*path, kind='all'*)Find the longest prefix of *path* contained in the dictionary.

Return tuple (*prefix, rest*), where both path entries are normalized according to the dictionary rules (i.e., these are lists representing normalized paths). *kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'. If the longest prefix is of a different kind, return (None, None).

**has\_entry**(*path, kind='all'*)

Determine if the path is in the dictionary.

*kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'.

**is\_branch\_path**(*path*)

Determine if the path is in the dictionary and points to a branch

**static is\_dictionary**(*obj*, *generic=True*)

Determine if the object is a dictionary.

**Parameters**

- **obj**
- **generic** (*bool*) – if False, passes only *Dictionary* (or subclasses) objects; otherwise, passes any dictionary-like object.

**Returns**

bool

**is\_leaf\_path**(*path*)

Determine if the path is in the dictionary and points to a leaf

**items**(*ordered=False*, *leafs=False*, *path\_kind='split'*, *wrap\_branches=True*)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iteritems**(*ordered=False*, *leafs=False*, *path\_kind='split'*, *wrap\_branches=True*)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iterkeys**(*ordered=False*, *leafs=False*, *path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**internodes**(*to\_visit='leafs'*, *ordered=False*, *include\_path=False*, *topdown=False*)

Iterate over nodes.

#### Parameters

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and *DictionaryPointer* for branches. If *include\_path==True*, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**intervales**(*ordered=False*, *leafs=False*, *wrap\_branches=True*)

Analog of *dict.values()*, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**keys**(*ordered=False*, *leafs=False*, *path\_kind='split'*)

Analog of *dict.keys()*, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**map\_self**(*func*, *to\_visit='leafs'*, *pass\_path=False*, *topdown=False*, *branch\_option='normalize'*)

Apply *func* to the nodes in the dictionary.

Note that any pointers to the replaced branches or their sub-branches will become invalid.

#### Parameters

- **func** (*callable*) – Mapping function. Leafs are passed by value, branches (if visited) are passed as *DictionaryPointer*.
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the map function.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *func*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.
- **branch\_option** (*str*) – If the function returns a dict-like object, determines how to incorporate into the dictionary; can be "normalize" (make a copy with normalized

paths and insert that), "copy" (make a copy without normalization), or "attach" (simply replace the value without copying and normalization)

**merge**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Attach source (**dict** or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to `add_entry()`, merges two branches instead of removing the old branch completely.

#### Parameters

- **source** (*dict* or *Dictionary*)
- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**nodes**(*to\_visit*='leafs', *ordered*=False, *include\_path*=False, *topdown*=False)

Iterate over nodes.

#### Parameters

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and *DictionaryPointer* for branches. If `include_path==True`, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**paths**(*ordered*=False, *topdown*=False, *path\_kind*='split')

Return list of all paths (leafs and nodes).

#### Parameters

- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **topdown** (*bool*) – If True, return node's leafs before its subtrees leafs.
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**pop**(*path*, *default*=None)

Analog of `dict.pop()`: remove value at *path* and return it if *path* in *D*, otherwise return *default*

Note that it never raises *KeyError*.

**setdefault**(*path*, *default*=None)

Analog of `dict.setdefault()`: `D.setdefault(k,d) -> D.get(k,d)`, also sets `D[k]=d` if *k* not in *D*.

**size**()

Return the total size of the dictionary (number of nodes)

**update**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Attach *source* (*dict* or other *Dictionary*) to a given branch; *source* is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to `add_entry()`, merges two branches instead of removing the old branch completely.

#### Parameters

- **source** (*dict* or *Dictionary*)
- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**updated**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Get a copy of the dictionary and attach a new branch to it.

Parameters are the same as in the *Dictionary.merge()*.

**values**(*ordered*=False, *leafs*=False, *wrap\_branches*=True)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**viewitems**(*ordered*=False, *leafs*=False, *path\_kind*='split', *wrap\_branches*=True)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**viewkeys**(*ordered*=False, *leafs*=False, *path\_kind*='split')

Analog of `dict.keys()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**viewvalues**(*ordered=False, leafs=False, wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

`pylablib.core.utils.dictionary.combine_dictionaries(dict, func, select='all', pass_missing=False)`

Combine several dictionaries element-wise (only for leafs) using a given function.

**Parameters**

- **dicts** (*list or tuple*) – list of dictionaries (*Dictionary* or `dict`) to be combined
- **func** (*callable*) – combination function. Takes a single argument, which is a list of elements to be combined.
- **select** (*str*) – determines which keys are selected for the resulting dictionary. Can be either "all" (only keep keys which are present in all the dictionaries), or "any" (keep keys which are present in at least one dictionary). Only keys that point to leafs count; if a key points to a non-leaf branch in some dictionary, it is considered absent from this dictionary.
- **pass\_missing** (*bool*) – if `select=="any"`, this parameter determines whether missing elements will be passed to *func* as `None`, or omitted entirely.

`class pylablib.core.utils.dictionary.PrefixTree(root=None, case_normalization=None, wildcard='*', matchcard='.', copy=True)`

Bases: *Dictionary*

Expansion of a *Dictionary* designed to store data related to prefixes.

Each branch node can have a leaf with a name given by wildcard ('\*' by default) or matchcard ('.' by default). Wildcard assumes that the branch node path is a prefix; matchcard assumes exact match. These leafs are inspected when specific prefix tree functions (*find\_largest\_prefix()* and *find\_all\_prefixes()*) are used.

**Parameters**

- **root** (*dict or Dictionary*) – Complete tree.
- **case\_normalization** (*str*) – Case normalization rules; can be `None` (no normalization, names are case-sensitive), 'lower' or 'upper'.
- **wildcard** (*str*) – Symbol for a wildcard entry.
- **matchcard** (*str*) – Symbol for a matchcard entry.
- **copy** (*bool*) – If True, make copy of the supplied data; otherwise, just make it the root.

**Warning:** If `copy==False`, the root data is already assumed to be normalized. If it isn't, the behavior might be incorrect.

**copy()**

Get a full copy the prefix tree

**find\_largest\_prefix**(*path*, *default=None*, *allow\_nomatch\_exact=True*, *return\_path=False*, *return\_subpath=False*)

Find the entry which is the largest prefix of a given path.

#### Parameters

- **path**
- **default** – Default value if the path isn't found.
- **allow\_nomatch\_exact** (*bool*) – If *True*, just element with the given path can be returned; otherwise, only elements stored under wildcards and matchcards are considered.
- **return\_path** (*bool*) – If *True*, return path to the element (i.e., the largest prefix) instead of the element itself.
- **return\_subpath** (*bool*) – If *True*, return tuple with a second element being part of the *path* left after subtraction of the prefix.

**find\_all\_prefixes**(*path*, *allow\_nomatch\_exact=True*, *return\_path=True*, *return\_subpath=False*)

Find list of all the entries which are prefixes of a given path.

#### Parameters

- **path**
- **default** – Default value if the path isn't found.
- **allow\_nomatch\_exact** (*bool*) – If *True*, just element with the given path can be returned; otherwise, only elements stored under wildcards and matchcards are considered.
- **return\_path** (*bool*) – If *True*, return path to the element (i.e., the largest prefix) instead of the element itself.
- **return\_subpath** (*bool*) – If *True*, return tuple with a second element being part of the *path* left after subtraction of the prefix.

**add\_entry**(*path*, *value*, *force=False*, *branch\_option='normalize'*)

Add value to a given path (overwrite leaf value if necessary).

Doesn't replace leaves with branches and vice-versa if *force==False*.

#### Parameters

- **path**
- **value**
- **force** (*bool*) – If *True*, change leaf into a branch and vice-versa; otherwise, raises *ValueError* if the conversion is necessary.
- **branch\_option** (*str*) –

Decides what to do if the value is dictionary-like:

- 'attach' – just attach the root,
- 'copy' – copy and attach,
- 'normalize' – copy while normalizing all the keys according to the current rules.

**as\_dict**(*style='nested', copy=True*)

Convert into a [dict](#) object.

**Parameters**

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**static as\_dictionary**(*obj, case\_normalization=None*)

Convert object into [Dictionary](#) with the given parameters.

If object is already a [Dictionary](#) (or its subclass), return unchanged, even if its parameters are different.

**as\_json**(*style='nested'*)

Convert into a JSON string.

**Parameters**

**style** (*str*) – Determines style of the result: - 'nested' – subtrees are turned into nested dictionaries, - 'flat' – single dictionary is formed with full paths as keys.

**as\_pandas**(*index\_key=True, as\_series=True*)

Convert into a pandas DataFrame or Series object.

**Parameters**

- **index\_key** (*bool*) – If False, create a 2-column table with the first column ("key") containing string path and the second column ("value") containing value; otherwise, move key to the table index.
- **as\_series** (*bool*) – If index\_key==True and as\_series==True, convert the resulting DataFrame into 1D Series (the key is the index); otherwise, keep it as a single-column table

**asdict**(*style='nested', copy=True*)

Convert into a [dict](#) object.

**Parameters**

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**branch\_copy**(*branch=""*)

Get a copy of the branch as a [Dictionary](#)

**branch\_pointer**(*branch=""*)

Get a [DictionaryPointer](#) of a given branch



**collect**(*paths*, *detach=False*, *ignore\_missing=True*)

Collect a set of subpaths into a separate dictionary.

**Parameters**

- **paths** – list or set of paths
- **detach** – if `True`, added branches are removed from this dictionary
- **ignore\_missing** – if `True`, ignore paths from the list which are not present in this dictionary; otherwise, raise a `KeyError`.

**del\_entry**(*path*)

Delete entry from the dictionary.

Return `True` if the path was present. Note that it never raises `KeyError`.

**detach**(*path*)

Remove a branch or a leaf from the current dictionary.

Branch is returned as a separate `Dictionary`. If *path* is missing, raise a `KeyError`.

**diff**(*other*)

Perform an element-wise comparison to another Dictionary.

If the other Dictionary has a different case sensitivity, raise `ValueError`.

**Returns**

`DictionaryDiff`

**static diff\_flatdict**(*first*, *second*)

Find the difference between flat `dict` objects.

**Returns**

`DictionaryDiff`

**filter\_self**(*pred*, *to\_visit='leafs'*, *pass\_path=False*, *topdown=False*)

Remove all the nodes from the dictionary for which *pred* returns `False`.

**Parameters**

- **pred** (*callable*) – Filter function. Leafs are passed to *pred* by value, branches (if visited) are passed as `DictionaryPointer`.
- **to\_visit** (*str*) – Can be `'leafs'`, `'branches'` or `'all'` and determines which parts of the dictionary passed to the predicate.
- **pass\_path** (*bool*) – If `True`, pass the node path (in the form of a normalized list) as a first argument to *pred*.
- **topdown** (*bool*) – If `True`, visit node and its leafs before its subtrees leafs.

**static find\_intersection**(*dicts*, *use\_flatten=False*)

Find intersection of multiple dictionaries.

**Parameters**

- **dicts** (*[Dictionary]*)
- **use\_flatten** (*bool*) – If `True` flatten all dictionaries before comparison (works faster for a large number of dictionaries).

**Returns**

`DictionaryIntersection`

**classmethod** `from_json(data, case_normalization=None)`

Convert JSON representations of a dictionary into a *Dictionary* object

**get**(*path*, *default=None*)

Analog of `dict.get()`: `D.get(k,d) -> D[k]` if `k` in `D` else `d`

**get\_entry**(*path*, *as\_pointer=False*)

Get entry at a given path

#### Parameters

- **path**
- **as\_pointer** (*bool*) – If `True` and entry is not a leaf, return *DictionaryPointer*; otherwise, return *Dictionary*

**get\_matching\_paths**(*pattern*, *wildkey='\**', *wildpath='\*\*'*', *only\_leaves=True*)

Get all paths in the tree that match the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If `True`, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, `only_leaves=False` is analogous to adding `wildpath` at the end of the pattern.

**get\_matching\_subtree**(*pattern*, *wildkey='\**', *wildpath='\*\*'*', *only\_leaves=True*)

Get a subtree containing nodes with paths matching the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If `True`, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, `only_leaves=False` is analogous to adding `wildpath` at the end of the pattern.

**get\_max\_prefix**(*path*, *kind='all'*)

Find the longest prefix of *path* contained in the dictionary.

Return tuple (*prefix*, *rest*), where both path entries are normalized according to the dictionary rules (i.e., these are lists representing normalized paths). *kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'. If the longest prefix is of a different kind, return (None, None).

**get\_path**()

**has\_entry**(*path*, *kind='all'*)

Determine if the path is in the dictionary.

*kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'.

**is\_branch\_path**(*path*)

Determine if the path is in the dictionary and points to a branch

**static is\_dictionary**(*obj*, *generic=True*)

Determine if the object is a dictionary.

#### Parameters

- **obj**
- **generic** (*bool*) – if False, passes only *Dictionary* (or subclasses) objects; otherwise, passes any dictionary-like object.

**Returns**

bool

**is\_leaf\_path**(*path*)

Determine if the path is in the dictionary and points to a leaf

**items**(*ordered=False, leafs=False, path\_kind='split', wrap\_branches=True*)

Analog of dict.items(), by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iteritems**(*ordered=False, leafs=False, path\_kind='split', wrap\_branches=True*)

Analog of dict.items(), by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iterkeys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of dict.keys(), iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**iternodes**(*to\_visit='leafs', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

**Parameters**

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.

- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and *DictionaryPointer* for branches. If `include_path==True`, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**itervalues**(*ordered=False*, *leafs=False*, *wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**keys**(*ordered=False*, *leafs=False*, *path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**map\_self**(*func*, *to\_visit='leafs'*, *pass\_path=False*, *topdown=False*, *branch\_option='normalize'*)

Apply *func* to the nodes in the dictionary.

Note that any pointers to the replaced branches or their sub-branches will become invalid.

#### Parameters

- **func** (*callable*) – Mapping function. Leafs are passed by value, branches (if visited) are passed as *DictionaryPointer*.
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the map function.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *func*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.
- **branch\_option** (*str*) – If the function returns a dict-like object, determines how to incorporate into the dictionary; can be "normalize" (make a copy with normalized paths and insert that), "copy" (make a copy without normalization), or "attach" (simply replace the value without copying and normalization)

**merge**(*source*, *path=""*, *overwrite=True*, *normalize\_paths=True*)

Attach source (*dict* or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v, p)` is equivalent to `D.add_entry(p, v, force=True)` in this case). Compared to `add_entry()`, merges two branches instead of removing the old branch completely.

**Parameters**

- **source** (*dict* or *Dictionary*)
- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**nodes**(*to\_visit='leaves', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

**Parameters**

- **to\_visit** (*str*) – Can be 'leaves', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leaves before its subtrees leaves.

**Yields**

Values for leaves and *DictionaryPointer* for branches. If *include\_path==True*, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**paths**(*ordered=False, topdown=False, path\_kind='split'*)

Return list of all paths (leaves and nodes).

**Parameters**

- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **topdown** (*bool*) – If True, return node's leaves before its subtrees leaves.
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**pop**(*path, default=None*)

Analog of `dict.pop()`: remove value at *path* and return it if *path* in *D*, otherwise return *default*

Note that it never raises *KeyError*.

**setdefault**(*path, default=None*)

Analog of `dict.setdefault()`: `D.setdefault(k,d) -> D.get(k,d)`, also sets `D[k]=d` if `k` not in `D`.

**size**()

Return the total size of the dictionary (number of nodes)

**update**(*source, path="", overwrite=True, normalize\_paths=True*)

Attach source (*dict* or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to *add\_entry()*, merges two branches instead of removing the old branch completely.

**Parameters**

- **source** (*dict* or *Dictionary*)

- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**updated**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Get a copy of the dictionary and attach a new branch to it.

Parameters are the same as in the [\*Dictionary.merge\(\)\*](#).

**values**(*ordered*=False, *leafs*=False, *wrap\_branches*=True)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into [\*DictionaryPointer\*](#) objects; otherwise, return them as nested built-in dictionaries

**viewitems**(*ordered*=False, *leafs*=False, *path\_kind*='split', *wrap\_branches*=True)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into [\*DictionaryPointer\*](#) objects; otherwise, return them as nested built-in dictionaries

**viewkeys**(*ordered*=False, *leafs*=False, *path\_kind*='split')

Analog of `dict.keys()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**viewvalues**(*ordered*=False, *leafs*=False, *wrap\_branches*=True)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)

- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

```
class pylablib.core.utils.dictionary.FilterTree(root=None, case_normalization=None,
                                                default=False, match_prefix=False, copy=True)
```

Bases: *Dictionary*

Expansion of a *Dictionary* designed to store hierarchical path filtering rules.

Store path templates and the corresponding values (usually True or False for a filter tree, but other values are possible). The *match()* method is then tested against this templates, and the value of the closest matching template (or default value, if none match) is returned. The templates can contain direct matches (e.g., "a/b/c", which matches only "a/b/c/" path), "\*" path entries for a single level wildcard (e.g., "a/\*/c" matches "a/b/c" or "a/d/c", but not "a/c" or "a/b/d/c"), or "\*\*\*" path entries for a multi-level wildcard (e.g., "a/\*\*/c" matches "a/b/c", "a/c", or "a/b/d/c"). The paths are always tested first for direct match, then for "\*" match, then for "\*\*\*" match starting from the smallest subpath matching "\*\*\*".

#### Parameters

- **root** (*dict* or *Dictionary*) – A filter tree or a list of filter tree paths (which are all assumed to be have the True value).s
- **case\_normalization** (*str*) – Case normalization rules; can be None (no normalization, names are case-sensitive), 'lower' or 'upper'.
- **default** – Default value to return if no match is found.
- **match\_prefix** – if True, match the result even if only its prefix matches the tree content (same effect as adding "/\*" to every tree path)
- **copy** (*bool*) – If True, make copy of the supplied data; otherwise, just make it the root.

**Warning:** If copy==False, the root data is already assumed to be normalized. If it isn't, the behavior might be incorrect.

#### copy()

Get a full copy the prefix tree

#### match(path)

Return the match result for the path

#### add\_entry(path, value, force=False, branch\_option='normalize')

Add value to a given path (overwrite leaf value if necessary).

Doesn't replace leaves with branches and vice-versa if force==False.

#### Parameters

- **path**
- **value**
- **force** (*bool*) – If True, change leaf into a branch and vice-versa; otherwise, raises *ValueError* if the conversion is necessary.
- **branch\_option** (*str*) –

Decides what to do if the value is dictionary-like:

- 'attach' – just attach the root,
- 'copy' – copy and attach,

- 'normalize' – copy while normalizing all the keys according to the current rules.

**as\_dict**(*style='nested', copy=True*)

Convert into a [dict](#) object.

**Parameters**

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**static as\_dictionary**(*obj, case\_normalization=None*)

Convert object into [Dictionary](#) with the given parameters.

If object is already a [Dictionary](#) (or its subclass), return unchanged, even if its parameters are different.

**as\_json**(*style='nested'*)

Convert into a JSON string.

**Parameters**

**style** (*str*) – Determines style of the result: - 'nested' – subtrees are turned into nested dictionaries, - 'flat' – single dictionary is formed with full paths as keys.

**as\_pandas**(*index\_key=True, as\_series=True*)

Convert into a pandas DataFrame or Series object.

**Parameters**

- **index\_key** (*bool*) – If False, create a 2-column table with the first column ("key") containing string path and the second column ("value") containing value; otherwise, move key to the table index.
- **as\_series** (*bool*) – If index\_key==True and as\_series==True, convert the resulting DataFrame into 1D Series (the key is the index); otherwise, keep it as a single-column table

**asdict**(*style='nested', copy=True*)

Convert into a [dict](#) object.

**Parameters**

- **style** (*str*) –

**Determines style of the result:**

- 'nested' – subtrees are turned into nested dictionaries,
- 'flat' – single dictionary is formed with full paths as keys.

- **copy** (*bool*) – If False and style=='nested', return the root dictionary.

**branch\_copy**(*branch=""*)

Get a copy of the branch as a [Dictionary](#)

**branch\_pointer**(*branch=""*)

Get a [DictionaryPointer](#) of a given branch



**collect**(*paths*, *detach*=False, *ignore\_missing*=True)

Collect a set of subpaths into a separate dictionary.

**Parameters**

- **paths** – list or set of paths
- **detach** – if True, added branches are removed from this dictionary
- **ignore\_missing** – if True, ignore paths from the list which are not present in this dictionary; otherwise, raise a [KeyError](#).

**del\_entry**(*path*)

Delete entry from the dictionary.

Return True if the path was present. Note that it never raises *KeyError*.

**detach**(*path*)

Remove a branch or a leaf from the current dictionary.

Branch is returned as a separate [Dictionary](#). If *path* is missing, raise a [KeyError](#).

**diff**(*other*)

Perform an element-wise comparison to another Dictionary.

If the other Dictionary has a different case sensitivity, raise [ValueError](#).

**Returns**

[DictionaryDiff](#)

**static diff\_flatdict**(*first*, *second*)

Find the difference between flat [dict](#) objects.

**Returns**

[DictionaryDiff](#)

**filter\_self**(*pred*, *to\_visit*='leafs', *pass\_path*=False, *topdown*=False)

Remove all the nodes from the dictionary for which *pred* returns False.

**Parameters**

- **pred** (*callable*) – Filter function. Leafs are passed to *pred* by value, branches (if visited) are passed as [DictionaryPointer](#).
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the predicate.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *pred*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

**static find\_intersection**(*dicts*, *use\_flatten*=False)

Find intersection of multiple dictionaries.

**Parameters**

- **dicts** ([\[Dictionary\]](#))
- **use\_flatten** (*bool*) – If True flatten all dictionaries before comparison (works faster for a large number of dictionaries).

**Returns**

[DictionaryIntersection](#)

**classmethod** `from_json(data, case_normalization=None)`

Convert JSON representations of a dictionary into a *Dictionary* object

**get**(*path*, *default=None*)

Analog of `dict.get()`: `D.get(k,d) -> D[k]` if `k` in `D` else `d`

**get\_entry**(*path*, *as\_pointer=False*)

Get entry at a given path

#### Parameters

- **path**
- **as\_pointer** (*bool*) – If `True` and entry is not a leaf, return *DictionaryPointer*; otherwise, return *Dictionary*

**get\_matching\_paths**(*pattern*, *wildkey='\**', *wildpath='\*\*'*', *only\_leaves=True*)

Get all paths in the tree that match the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If `True`, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, `only_leaves=False` is analogous to adding `wildpath` at the end of the pattern.

**get\_matching\_subtree**(*pattern*, *wildkey='\**', *wildpath='\*\*'*', *only\_leaves=True*)

Get a subtree containing nodes with paths matching the provided pattern.

#### Parameters

- **wildkey** (*str*) – Pattern symbol that matches any key.
- **wildpath** (*str*) – Pattern symbol that matches any subpath (possibly empty).
- **only\_leaves** (*bool*) – If `True`, only check leaf paths; otherwise, check subtree paths (i.e., incomplete leaf paths) as well. Basically, `only_leaves=False` is analogous to adding `wildpath` at the end of the pattern.

**get\_max\_prefix**(*path*, *kind='all'*)

Find the longest prefix of *path* contained in the dictionary.

Return tuple (*prefix*, *rest*), where both path entries are normalized according to the dictionary rules (i.e., these are lists representing normalized paths). *kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'. If the longest prefix is of a different kind, return (None, None).

**get\_path**()

**has\_entry**(*path*, *kind='all'*)

Determine if the path is in the dictionary.

*kind* determines which kind of path to consider and can be 'leaf', 'branch' or 'all'.

**is\_branch\_path**(*path*)

Determine if the path is in the dictionary and points to a branch

**static is\_dictionary**(*obj*, *generic=True*)

Determine if the object is a dictionary.

#### Parameters

- **obj**
- **generic** (*bool*) – if False, passes only *Dictionary* (or subclasses) objects; otherwise, passes any dictionary-like object.

**Returns**

bool

**is\_leaf\_path**(*path*)

Determine if the path is in the dictionary and points to a leaf

**items**(*ordered=False, leafs=False, path\_kind='split', wrap\_branches=True*)

Analog of dict.items(), by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iteritems**(*ordered=False, leafs=False, path\_kind='split', wrap\_branches=True*)

Analog of dict.items(), by default iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**iterkeys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of dict.keys(), iterating only over the immediate children of the root.

**Parameters**

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**iternodes**(*to\_visit='leafs', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

**Parameters**

- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.

- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.

#### Yields

Values for leafs and *DictionaryPointer* for branches. If `include_path==True`, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**itervalues**(*ordered=False, leafs=False, wrap\_branches=True*)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**keys**(*ordered=False, leafs=False, path\_kind='split'*)

Analog of `dict.keys()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as ‘flat’ dictionary); otherwise, loop over immediate children (i.e., behave as ‘nested’ dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**map\_self**(*func, to\_visit='leafs', pass\_path=False, topdown=False, branch\_option='normalize'*)

Apply *func* to the nodes in the dictionary.

Note that any pointers to the replaced branches or their sub-branches will become invalid.

#### Parameters

- **func** (*callable*) – Mapping function. Leafs are passed by value, branches (if visited) are passed as *DictionaryPointer*.
- **to\_visit** (*str*) – Can be 'leafs', 'branches' or 'all' and determines which parts of the dictionary passed to the map function.
- **pass\_path** (*bool*) – If True, pass the node path (in the form of a normalized list) as a first argument to *func*.
- **topdown** (*bool*) – If True, visit node and its leafs before its subtrees leafs.
- **branch\_option** (*str*) – If the function returns a dict-like object, determines how to incorporate into the dictionary; can be "normalize" (make a copy with normalized paths and insert that), "copy" (make a copy without normalization), or "attach" (simply replace the value without copying and normalization)

**merge**(*source, path="", overwrite=True, normalize\_paths=True*)

Attach source (*dict* or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v, p)` is equivalent to `D.add_entry(p, v, force=True)` in this case). Compared to `add_entry()`, merges two branches instead of removing the old branch completely.

**Parameters**

- **source** (*dict* or *Dictionary*)
- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**nodes**(*to\_visit='leaves', ordered=False, include\_path=False, topdown=False*)

Iterate over nodes.

**Parameters**

- **to\_visit** (*str*) – Can be 'leaves', 'branches' or 'all' and determines which parts of the dictionary are visited.
- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **include\_path** (*bool*) – Include in the return value.
- **topdown** (*bool*) – If True, visit node and its leaves before its subtrees leaves.

**Yields**

Values for leaves and *DictionaryPointer* for branches. If *include\_path==True*, yields tuple (*path*, *value*), where *path* is in the form of a normalized list.

**paths**(*ordered=False, topdown=False, path\_kind='split'*)

Return list of all paths (leaves and nodes).

**Parameters**

- **ordered** (*bool*) – If True, loop over paths in alphabetic order.
- **topdown** (*bool*) – If True, return node's leaves before its subtrees leaves.
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**pop**(*path, default=None*)

Analog of `dict.pop()`: remove value at *path* and return it if *path* in *D*, otherwise return *default*

Note that it never raises *KeyError*.

**setdefault**(*path, default=None*)

Analog of `dict.setdefault()`: `D.setdefault(k,d) -> D.get(k,d)`, also sets `D[k]=d` if `k` not in `D`.

**size**()

Return the total size of the dictionary (number of nodes)

**update**(*source, path="", overwrite=True, normalize\_paths=True*)

Attach source (*dict* or other *Dictionary*) to a given branch; source is automatically deep-copied.

If *source* is not a dictionary, simply assign it (i.e., `D.merge(v,p)` is equivalent to `D.add_entry(p,v, force=True)` in this case). Compared to *add\_entry()*, merges two branches instead of removing the old branch completely.

**Parameters**

- **source** (*dict* or *Dictionary*)

- **branch** (*tuple* or *str*) – Destination path.
- **overwrite** (*bool*) – If True, replaces the old entries with the new ones (it only matters for leaf assignments).
- **normalize\_paths** (*bool*) – If True and the dictionary isn't case sensitive, perform normalization if the *source*.

**updated**(*source*, *path*="", *overwrite*=True, *normalize\_paths*=True)

Get a copy of the dictionary and attach a new branch to it.

Parameters are the same as in the [\*Dictionary.merge\(\)\*](#).

**values**(*ordered*=False, *leafs*=False, *wrap\_branches*=True)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into [\*DictionaryPointer\*](#) objects; otherwise, return them as nested built-in dictionaries

**viewitems**(*ordered*=False, *leafs*=False, *path\_kind*='split', *wrap\_branches*=True)

Analog of `dict.items()`, by default iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)
- **wrap\_branches** (*bool*) – if True, wrap sub-branches into [\*DictionaryPointer\*](#) objects; otherwise, return them as nested built-in dictionaries

**viewkeys**(*ordered*=False, *leafs*=False, *path\_kind*='split')

Analog of `dict.keys()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)
- **path\_kind** (*str*) – either "split" (each path is a tuple of individual keys), or "joined" (each path is a single string)

**viewvalues**(*ordered*=False, *leafs*=False, *wrap\_branches*=True)

Analog of `dict.values()`, iterating only over the immediate children of the root.

#### Parameters

- **ordered** (*bool*) – If True, loop over keys in alphabetic order.
- **leafs** (*bool*) – If True, loop over leaf nodes (i.e., behave as 'flat' dictionary); otherwise, loop over immediate children (i.e., behave as 'nested' dictionary)

- **wrap\_branches** (*bool*) – if True, wrap sub-branches into *DictionaryPointer* objects; otherwise, return them as nested built-in dictionaries

**class** pylablib.core.utils.dictionary.**PrefixShortcutTree**(shortcuts=None)

Bases: *object*

Convenient storage for dictionary path shortcuts.

#### Parameters

**shortcuts** (*dict*) – Dictionary of shortcuts {shortcut: full\_path}.

**copy**()

Return full copy

**add\_shortcut**(source, dest, exact=False)

Add a single shortcut.

#### Parameters

- **source** – Shortcut path.
- **dest** – expanded path corresponding to the shortcut.
- **exact** (*bool*) – If True, the shortcut works only for the exact path; otherwise, it works for any path with ‘source’ as a prefix.

**add\_shortcuts**(shortcuts, exact=False)

Add a dictionary of shortcuts {shortcut: full\_path}.

Arguments are the same as in *PrefixShortcutTree.add\_shortcut()*.

**remove\_shortcut**(source)

Remove a shortcut from the tree

**updated**(shortcuts, exact=False)

Make a copy and add additional shortcuts.

Arguments are the same as in *PrefixShortcutTree.add\_shortcuts()*.

**class** pylablib.core.utils.dictionary.**DictionaryNode**(\*\*vargs)

Bases: *object*

pylablib.core.utils.dictionary.**dict\_to\_object\_local**(data, name=None, object\_generator=<function \_default\_object\_generator>)

**class** pylablib.core.utils.dictionary.**ItemAccessor**(getter=None, setter=None, deleter=None, iterator=None, contains\_checker='auto', normalize\_names=True, path\_separator=None, missing\_error=None)

Bases: *object*

Simple wrapper which implements array interface using supplied methods.

Also has an option to normalize requested paths (enabled by default)

#### Parameters

- **getter** – method for getting values (None means none is supplied, so getting raises an error)
- **setter** – method for setting values (None means none is supplied, so setting raises an error)

- **deleter** – method for deleting values (`None` means none is supplied, so deleting raises an error)
- **contains\_checker** – method for checking if variable is present (`None` means none is supplied, so checking containment raises an error; "auto" means that getter raising `KeyError` is used for checking)
- **normalize\_names** – if `True`, normalize a supplied path using the standard `Dictionary` rules and join it into a single string using the supplied separator
- **path\_separator** – path separator regex used for splitting and joining the supplied paths (by default, the standard `"/"` separator)
- **missing\_error** – if not `None`, specifies the error raised on the missing value; used in `__contains__`, `get()` and `setdefault()` to determine if the value is missing

`get(name, default=None)`

`setdefault(name, default=None)`

## pylablib.core.utils.files module

Utilities for working with the file system: creating/removing/listing folders, comparing folders and files, working with zip archives.

`pylablib.core.utils.files.eof(f, strict=False)`

Standard EOF function.

Return `True` if the the marker is at the end of the file. If `strict==True`, only return `True` if the marker is exactly at the end of file; otherwise, return `True` if it's at the end of further.

`pylablib.core.utils.files.get_file_creation_time(path, timestamp=True)`

Try to find a file creation time. Return current time if an error occurs.

If `timestamp==True`, return UNIX timestamp; otherwise, return `datetime.datetime`.

`pylablib.core.utils.files.get_file_modification_time(path, timestamp=True)`

Try to find a file modification time. Return current time if an error occurs.

If `timestamp==True`, return UNIX timestamp; otherwise, return `datetime.datetime`

`pylablib.core.utils.files.touch(fname, times=None)`

Update file access and modification times.

### Parameters

**times** (`tuple`) – Access and modification times; if `times` is `None`, use current time.

`pylablib.core.utils.files.generate_indexed_filename(name_format, idx_start=0, folder='')`

Generate an unused indexed filename in `folder`.

The name has `name_format` (using standard Python `format()` rules, e.g., `"data_{:03d}.dat"`), and the index starts with `idx_start`.

`pylablib.core.utils.files.generate_prefixed_filename(prefix="", suffix="", idx_start=None, idx_fmt='d', folder=None)`

Generate an unused filename with the given `prefix` and `suffix` in the given `folder`.

By default, the format is `prefix_{:d}_suffix`, where the parameter is the index starting with `idx_start`. If `idx_start` is `None`, first check simply `prefix+suffix` name before using numbered indices.



```
pylablib.core.utils.files.generate_temp_filename(prefix='__tmp__', idx_start=0, idx_template='d',
                                                folder="")
```

Generate a temporary filename with a given prefix.

*idx\_template* is the number index format (only the parameter itself, not the whole string).

```
pylablib.core.utils.files.fullsplit(path, ignore_empty=True)
```

Split path into a list.

If *ignore\_empty*==True, exclude empty folder names.

```
pylablib.core.utils.files.normalize_path(p)
```

Normalize filesystem path (case and origin). If two paths are identical, they should be equal when normalized

```
pylablib.core.utils.files.case_sensitive_path()
```

Check if OS path names are case-sensitive (e.g., Linux)

```
pylablib.core.utils.files.paths_equal(a, b)
```

Determine if the two paths are equal (can be local or have different case)

```
pylablib.core.utils.files.relative_path(a, b, check_paths=True)
```

Determine return path *a* as seen from *b*.

If *check\_paths*==True, check if *a* is contained in *b* and raise the `OSError` if it isn't.

```
pylablib.core.utils.files.is_path_valid(p)
```

Check if the string is a valid path.

Not guaranteed to have complete success rate, but catches most likely errors (invalid characters, reserved file names, too long, etc.) Does not check if the path actually exists or if it can be written into.

```
class pylablib.core.utils.files.TempFile(folder="", name=None, mode='w', wait_time=None,
                                         rep_time=None)
```

Bases: `object`

Temporary file context manager.

Upon creation, generate an unused temporary filename. Upon entry, create the file using supplied mode and return self. Upon exit, close and remove the file.

Can be mostly substituted by `tempfile.TemporaryFile()`, but generates file locally, and with specified/determined name. Preserved largely for legacy reasons.

#### Parameters

- **folder** (*str*) – Containing folder.
- **name** (*str*) – File name. If None, generate new temporary name.
- **mode** (*str*) – File opening mode.
- **wait\_time** (*float*) – Waiting time between attempts to create the file if the first try fails.
- **rep\_time** (*int*) – Number of attempts to create the file if the first try fails.

**f**

File object.

**name**

File name.

**Type**

*str*

**full\_name**

File name including containing folder.

**Type**

`str`

```
pylablib.core.utils.files.copy_file(source, dest, overwrite=True, cmp_on_overwrite=True,
                                     preserve_metadata=True)
```

Copy file, creating a containing folder if necessary. Return `True` if the operation was performed.

**Parameters**

- **overwrite** (*bool*) – If `True`, overwrite existing file.
- **cmp\_on\_overwrite** (*bool*) – If `True` and the two files are compared to be the same, don't perform overwrite.
- **preserve\_metadata** (*bool*) – If `True`, preserve file metadata (such as creation time) by using `shutil.copy2()`; otherwise, use `shutil.copy()`

```
pylablib.core.utils.files.move_file(source, dest, overwrite=True, cmp_on_overwrite=True,
                                     preserve_if_not_move=False)
```

Move file, creating a containing folder if necessary. Returns `True` if the operation was performed.

**Parameters**

- **overwrite** (*bool*) – If `True`, overwrite existing file (if the existing file isn't overwritten, preserve the original).
- **cmp\_on\_overwrite** (*bool*) – If `True` and the two files are compared to be the same, don't perform overwrite.
- **preserve\_if\_not\_move** (*bool*) – If `True` and the files are identical, preserve the original.

```
pylablib.core.utils.files.ensure_dir_singlelevel(path, error_on_file=True)
```

```
pylablib.core.utils.files.ensure_dir(path, error_on_file=True)
```

Ensure that the folder exists (create a new one if necessary).

If `error_on_file==True`, raise `OSError` if there's a file with the same name.

```
pylablib.core.utils.files.remove_dir(path, error_on_file=True)
```

Remove the folder recursively if it exists.

If `error_on_file==True`, raise `OSError` if there's a file with the same name.

```
pylablib.core.utils.files.remove_dir_if_empty(path, error_on_file=True)
```

Remove the folder only if it's empty.

If `error_on_file==True`, raise `OSError` if there's a file with the same name.

```
pylablib.core.utils.files.clean_dir(path, error_on_file=True)
```

Remove the folder and then recreate it.

If `error_on_file==True`, raise `OSError` if there's a file with the same name.

```
class pylablib.core.utils.files.FolderList(folders, files)
```

Bases: `FolderList`

Describes folder content

**files****folders**

```
pylablib.core.utils.files.list_dir(folder="", folder_filter=None, file_filter=None, separate_kinds=True,
                                     error_on_file=True)
```

Return folder content filtered by *folder\_filter* and *file\_filter*.

**Parameters**

- **folder** (*str*) – Path to the folder.
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **separate\_kinds** (*bool*) – if True, return *FolderList* with files and folder separate; otherwise, return a single list (works much faster).
- **error\_on\_file** (*bool*) – if True, raise *OSError* if there's a file with the same name as the target folder.

```
pylablib.core.utils.files.dir_empty(folder, folder_filter=None, file_filter=None, level='single',
                                     error_on_file=True)
```

Check if the folder is empty (only checks content filtered by *folder\_filter* and *file\_filter*).

**Parameters**

- **folder** (*str*) – Path to the folder.
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **level** (*str*) – if 'single', check only immediate folder content; if 'recursive', follow recursively in all folders passing *folder\_filter*.
- **error\_on\_file** (*bool*) – if True, raise *OSError* if there's a file with the same name as the target folder.

```
pylablib.core.utils.files.walk_dir(folder, folder_filter=None, file_filter=None, rel_path=True,
                                     topdown=True, visit_folder_filter=None, max_depth=None)
```

Modification of `os.walk()` function.

Acts in a similar way, but *followlinks* is always False and errors of `os.listdir()` are always passed.

**Parameters**

- **folder** (*str*) – Path to the folder.
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **rel\_path** (*bool*) – If True, the returned folder path is specified relative to the initial path.
- **topdown** (*bool*) – If True, return folder before its subfolders.

- **visit\_folder\_filter** – Filter for visiting folders (more description at [string.get\\_string\\_filter\(\)](#)). If not `None`, specifies filter for visiting folders which is different from `folder_filter` (filter for returned folders).
- **max\_depth** (*int*) – If not `None`, limits the recursion depth.

#### Yields

For each folder (including the original) yields a tuple (**folder\_path**, **folders**, **files**), where *folder\_path* is the containing folder name and *folders* and *files* are its content (similar to [list\\_dir\(\)](#)).

```
pylablib.core.utils.files.list_dir_recursive(folder, folder_filter=None, file_filter=None,
                                             topdown=True, visit_folder_filter=None,
                                             max_depth=None)
```

Recursive walk analog of [list\\_dir\(\)](#).

Parameters are the same as [walk\\_dir\(\)](#).

#### Returns

[FolderList](#)

```
pylablib.core.utils.files.copy_dir(source, dest, folder_filter=None, file_filter=None, overwrite=True,
                                   cmp_on_overwrite=True, preserve_metadata=True)
```

Copy files satisfying the filtering conditions.

#### Parameters

- **source** (*str*) – Source path.
- **dest** (*str*) – Destination path.
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **overwrite** (*bool*) – If `True`, overwrite existing files.
- **cmp\_on\_overwrite** (*bool*) – If `True` and the two files are compared to be the same, don't perform overwrite.
- **preserve\_metadata** (*bool*) – If `True`, preserve file metadata (such as creation time) by using [shutil.copy2\(\)](#); otherwise, use [shutil.copy\(\)](#)

```
pylablib.core.utils.files.move_dir(source, dest, folder_filter=None, file_filter=None, overwrite=True,
                                   cmp_on_overwrite=True, preserve_if_not_move=False)
```

Move files satisfying the filtering conditions.

#### Parameters

- **source** (*str*) – Source path.
- **dest** (*str*) – Destination path.
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).

- **overwrite** (*bool*) – If *True*, overwrite existing files (if the existing file isn't overwritten, preserve the original).
- **cmp\_on\_overwrite** (*bool*) – If *True* and the two files are compared to be the same, don't perform overwrite.
- **preserve\_if\_not\_move** (*bool*) – If *True* and the files are identical, preserve the original.

`pylablib.core.utils.files.combine_diff(d1, d2)`

`pylablib.core.utils.files.cmp_dirs(a, b, folder_filter=None, file_filter=None, shallow=True, return_difference=False)`

Compare the folders based on the content filtered by *folder\_filter* and *file\_filter*.

#### Parameters

- **a** (*str*) – First folder path
- **b** (*str*) – Second folder path
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **shallow** – If *True*, do shallow comparison of the files (see [filecmp.cmp\(\)](#)).
- **return\_difference** – If *False*, simply return *bool*; otherwise, return difference type ('=', '+', '-' or '\*').

`pylablib.core.utils.files.retry_copy(source, dest, overwrite=True, cmp_on_overwrite=True, preserve_metadata=True, try_times=5, delay=0.3)`

Retrying version of [copy\\_file\(\)](#).

If the operation raises error, wait for *delay* (in seconds) and call it again. Try total of *try\_times* times.

`pylablib.core.utils.files.retry_move(source, dest, overwrite=True, cmp_on_overwrite=True, preserve_if_not_move=False, try_times=5, delay=0.3)`

Retrying version of [move\\_file\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

`pylablib.core.utils.files.retry_remove(path, try_times=5, delay=0.3)`

Retrying version of [os.remove\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

`pylablib.core.utils.files.retry_ensure_dir(path, error_on_file=True, try_times=5, delay=0.3)`

Retrying version of [ensure\\_dir\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

`pylablib.core.utils.files.retry_copy_dir(source, dest, folder_filter=None, file_filter=None, overwrite=True, cmp_on_overwrite=True, preserve_metadata=True, try_times=5, delay=0.3)`

Retrying version of [copy\\_dir\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

`pylablib.core.utils.files.retry_move_dir(source, dest, folder_filter=None, file_filter=None, overwrite=True, cmp_on_overwrite=True, preserve_if_not_move=False, try_times=5, delay=0.3)`

Retrying version of [move\\_dir\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

`pylablib.core.utils.files.retry_remove_dir(path, error_on_file=True, try_times=5, delay=0.3)`

Retrying version of [remove\\_dir\(\)](#) (see [retry\\_copy\(\)](#) for details on retrying).

```
pylablib.core.utils.files.retry_remove_dir_if_empty(path, error_on_file=True, try_times=5,
                                                    delay=0.3)
```

Retrying version of `remove_dir_if_empty()` (see `retry_copy()` for details on retrying).

```
pylablib.core.utils.files.retry_clean_dir(path, error_on_file=True, try_times=5, delay=0.3)
```

Retrying version of `clean_dir()` (see `retry_copy()` for details on retrying).

```
pylablib.core.utils.files.zip_folder(zip_path, source_path, inside_path="", folder_filter=None,
                                     file_filter=None, mode='a', compression=8, compresslevel=None)
```

Add a folder into a zip archive.

#### Parameters

- **zip\_path** (*str*) – Path to the .zip file.
- **source\_path** (*str*) – Path to the source folder.
- **inside\_path** (*str*) – Destination path inside the zip archive.
- **folder\_filter** – Folder filter function (more description at `string.get_string_filter()`).
- **file\_filter** – File filter function (more description at `string.get_string_filter()`).
- **mode** (*str*) – Zip archive adding mode (see `zipfile.ZipFile`).
- **compression** – Zip archive compression (see `zipfile.ZipFile`).
- **compresslevel** – Zip archive compression level (see `zipfile.ZipFile`); ignored for Python version below 3.7.

```
pylablib.core.utils.files.zip_file(zip_path, source_path, inside_name=None, mode='a', compression=8,
                                   compresslevel=None)
```

Add a file into a zip archive.

#### Parameters

- **zip\_path** (*str*) – Path to the .zip file.
- **source\_path** (*str*) – Path to the source file.
- **inside\_name** (*str*) – Destination file name inside the zip archive (source name on the top level by default).
- **mode** (*str*) – Zip archive adding mode (see `zipfile.ZipFile`).
- **compression** – Zip archive compression (see `zipfile.ZipFile`).
- **compresslevel** – Zip archive compression level (see `zipfile.ZipFile`); ignored for Python version below 3.7.

```
pylablib.core.utils.files.zip_multiple_files(zip_path, source_paths, inside_names=None, mode='a',
                                             compression=8, compresslevel=None)
```

Add a multiple files into a zip archive.

#### Parameters

- **zip\_path** (*str*) – Path to the .zip file.
- **source\_paths** (*[str]*) – List of path to the source files.
- **inside\_names** (*[str]* or *None*) – List of destination file names inside the zip archive (source name on the top level by default).

- **mode** (*str*) – Zip archive adding mode (see `zipfile.ZipFile`).
- **compression** – Zip archive compression (see `zipfile.ZipFile`).
- **compresslevel** – Zip archive compression level (see `zipfile.ZipFile`); ignored for Python version below 3.7.

```
pylablib.core.utils.files.unzip_folder(zip_path, dest_path, inside_path="", folder_filter=None,
                                       file_filter=None)
```

Extract a folder from a zip archive (create containing folder if necessary).

#### Parameters

- **zip\_path** (*str*) – Path to the .zip file.
- **dest\_path** (*str*) – Path to the destination folder.
- **inside\_path** (*str*) – Source path inside the zip archive; extracted data paths are relative (i.e., they don't include *inside\_path*).
- **folder\_filter** – Folder filter function (more description at [string.get\\_string\\_filter\(\)](#)).
- **file\_filter** – File filter function (more description at [string.get\\_string\\_filter\(\)](#)).

```
pylablib.core.utils.files.unzip_file(zip_path, dest_path, inside_path)
```

Extract a file from a zip archive (create containing folder if necessary).

#### Parameters

- **zip\_path** (*str*) – Path to the .zip file.
- **dest\_path** (*str*) – Destination file path.
- **inside\_path** (*str*) – Source path inside the zip archive.

## pylablib.core.utils.funcargparse module

Contains routines for checking arguments passed into a function for better flexibility.

```
pylablib.core.utils.funcargparse.parameter_value_error(par_val, par_name, message=None,
                                                         error_type=None)
```

Raise parameter value error (`ValueError` by default).

```
pylablib.core.utils.funcargparse.parameter_range_error(par_val, par_name, par_set=None,
                                                         message=None, error_type=None)
```

Raise parameter range error (`ValueError` by default).

```
pylablib.core.utils.funcargparse.check_parameter_range(par_val, par_name, par_set, message=None,
                                                         error_type=None)
```

Raise error if *par\_val* is not in in the *par\_set* (*par\_name* is used in the error message).

```
pylablib.core.utils.funcargparse.getdefault(value, default_value, unassigned_value=None,
                                              conflict_action='ignore', message=None,
                                              error_type=None)
```

Analog of dict's `getdefault`.

If *value* is *unassigned\_value*, return *default\_value* instead. If *conflict\_action*=='error' and *value*!=*default\_value*, raise value error using *message* and *error\_type*.

`pylablib.core.utils.funcargparse.is_sequence(value, sequence_type='builtin;nostring')`

Check if *value* is a sequence.

*sequence\_type* is semicolon separated list of possible sequence types:

- 'builtin' - list, tuple or str
- 'nostring' - str is not allowed
- 'array' - list, tuple or `numpy.ndarray`
- 'indexable' - anything which can be indexed
- 'haslength' - anything with length property

`pylablib.core.utils.funcargparse.make_sequence(element, length=1, sequence_type='list')`

Turn element into a sequence of *sequence\_type* ('list' or 'tuple') repeated *length* times.

`pylablib.core.utils.funcargparse.as_sequence(value, multiply_length=1, allowed_type='builtin;nostring', wrapping_type='list', length_conflict_action='ignore', message=None, error_type=None)`

Ensure that *value* is a sequence.

If *value* is not a sequence of *allowed\_type* (as checked by `is_sequence()`), turn it into a sequence specified by *wrapping\_type* and *multiply\_length*.

If *value* is a sequence and *length\_conflict\_action*=='error', raise error with *error\_type* and *error\_message* if the length doesn't match *multiply\_length*. Otherwise, return value unchanged.

## pylablib.core.utils.functions module

Utilities for dealing with function, methods and function signatures.

**class** `pylablib.core.utils.functions.FunctionSignature`(*arg\_names=None, defaults=None, varg\_name=None, kwarg\_name=None, kwonly\_arg\_names=None, cls=None, obj=None, name=None, doc=None*)

Bases: `object`

Description of a function signature, including name, argument names, default values, names of varg and kwarg arguments, class and object (for methods) and docstring.

### Parameters

- **arg\_names** (*list*) – Names of the arguments.
- **default** (*dict*) – Dictionary {name: value} of default values.
- **varg\_name** (*str*) – Name of \*varg parameter (None means no such parameter).
- **kwarg\_name** (*str*) – Name of \*\*kwarg parameter (None means no such parameter).
- **cls** – Caller class, for methods.
- **obj** – Caller object, for methods.
- **name** (*str*) – Function name.
- **doc** (*str*) – Function docstring.



**get\_defaults\_list()**

Get list of default values for arguments in the order specified in the signature.

**signature**(*pass\_order=None*)

Get string containing a signature (arguments list) of the function (call or definition), including *\*vargs* and *\*\*kwargs*.

If *pass\_order* is not *None*, it specifies the order in which the arguments are passed.

**wrap\_function**(*func, pass\_order=None*)

Wrap a function *func* into a containing function with this signature.

Sets function name, argument names, default values, object and class (for methods) and docstring. If *pass\_order* is not *None*, it determines the order in which the positional arguments are passed to the wrapped function.

**as\_kwargs**(*args, kwargs, add\_defaults=False, exclude=None*)

Turn *args* and *kwargs* into a single *kwargs* dictionary using the names of positional arguments.

If *add\_defaults==True*, add all the non-specified default arguments as well. If the function takes *\*args* argument and some of the supplied arguments go there, place them into a list under *"\*"* key in the result. If *exclude* is not *None* is specifies arguments which should be excluded.

**arg\_value**(*argname, args=None, kwargs=None*)

Get the value of the argument with the given name for given *args* and *kwargs*

**mandatory\_args\_num()**

Get minimal number of arguments which have to be passed to the function.

The mandatory arguments are the ones which are not bound to caller object (i.e., not *self*) and don't have default values.

**max\_args\_num**(*include\_positional=True, include\_keywords=True*)

Get maximal number of arguments which can be passed to the function.

**Parameters**

- **include\_positional** (*bool*) – If *True* and function accepts *\*vargs*, return *None* (unlimited number of arguments).
- **include\_keywords** (*bool*) – If *True* and function accepts *\*\*kwargs*, return *None* (unlimited number of arguments).

**static from\_function**(*func, follow\_wrapped=True*)

Get signature of the given function or method.

If *follow\_wrapped==True*, follow *\_\_wrapped\_\_* attributes until the innermost function (useful for getting signatures of functions wrapped using *functools* methods).

**copy()**

Return a copy

**as\_simple\_func()**

Turn the signature into a simple function (as opposed to a bound method).

If the signature corresponds to a bound method, get rid of the first argument in the signature (*self*) and the bound object. Otherwise, return unchanged.

```
static merge(inner, outer, add_place='front', merge_duplicates=True, overwrite=None,
             hide_outer_obj=False)
```

Merge two signatures (used for wrapping functions).

The signature describes the function would take arguments according to the *outer* signature and pass them according to the *inner* signature.

**The arguments are combined:**

- if `add_place=='front'`, the outer arguments are placed in the beginning, followed by inner arguments not already listed;
- if `add_place=='back'`, the inner arguments are placed in the beginning, followed by outer arguments not already listed.

The default values are joined, with the outer values superseding the inner values.

*overwrite* is a set or a list specifying which inner parameters are overwritten by the outer. It includes 'name', 'doc', 'cls', 'obj', 'varg\_name' and 'kwarg\_name'; the default value is all parameters.

If the inner signature is a bound method and `hide_inner_obj==True`, treat it as a function (with `self` argument missing). In this case, the wrapped signature `.obj` field will be `None`.

**Returns**

(signature, pass\_order)

*pass\_order* is the order in which the arguments of the combined signature may be passed to the inner signature; it may be different from the signature order if `add_place=='front'`. If `merge_duplicates==True`, duplicate entries in *pass\_order* are omitted; otherwise, they're repeated.

**Return type**

tuple

```
pylablib.core.utils.functions.funcsig(func, follow_wrapped=True)
```

Return a function signature object

```
pylablib.core.utils.functions.getargsfrom(source, **merge_params)
```

Decorator factory.

Returns decorator that conforms function signature to the source function. `**merge_params` are passed to the `FunctionSignature.merge()` method merging wrapped and source signature.

The default behavior (conforming parameter names, default values args and kwargs names) is useful for wrapping universal functions like `g(*args, **kwargs)`.

Example:

```
def f(x, y=2):
    return x+y

@getargsfrom(f)
def g(*args): # Now g has the same signature as f, including parameter names and
    ↪ default values.
    return prod(args)
```

```
pylablib.core.utils.functions.call_cut_args(func, *args, **kwargs)
```

Call *func* with the given arguments, omitting the ones that don't fit its signature.

`pylablib.core.utils.functions.getattr_call(obj, attr_name, *args, **kwargs)`

Call the getter for the attribute *attr\_name* of *obj*.

If the attribute is a property, pass *\*args* and *\*\*kwargs* to the getter (*fget*); otherwise, ignore them.

`pylablib.core.utils.functions.setattr_call(obj, attr_name, *args, **kwargs)`

Call the setter for the attribute *attr\_name* of *obj*.

If the attribute is a property, pass *\*args* and *\*\*kwargs* to the setter (*fset*); otherwise, the set value is assumed to be either the first argument, or the keyword argument with the name 'value'.

`pylablib.core.utils.functions.delattr_call(obj, attr_name, *args, **kwargs)`

Call the deleter for the attribute *attr\_name* of *obj*.

If the attribute is a property, pass *\*args* and *\*\*kwargs* to the deleter (*fdel*); otherwise, ignore them.

**class** `pylablib.core.utils.functions.IObjectCall`

Bases: `object`

Universal interface for object method call (makes methods, attributes and properties look like methods).

Should be called with an object as a first argument.

**class** `pylablib.core.utils.functions.MethodObjectCall(method)`

Bases: `IObjectCall`

Object call created from an object method.

#### Parameters

**method** – Either a method object or a method name which is used for the call.

**class** `pylablib.core.utils.functions.AttrObjectCall(name, as_getter)`

Bases: `IObjectCall`

Object call created from an object attribute (makes attributes and properties look like methods).

#### Parameters

- **name** (*str*) – Attribute name.
- **as\_getter** (*bool*) – If *True*, call the getter when invoked; otherwise, call the setter.

If an attribute is a simple attribute, than getter gets no arguments and setter gets one argument (either the first argument, or the keyword argument named 'value'). If it's a property, pass all the parameters to the property call.

**class** `pylablib.core.utils.functions.IObjectProperty`

Bases: `object`

Universal interface for an object property (makes methods, attributes and properties look like properties).

Can be used to get, set or remove a property.

**get**(*obj*, *params=None*)

**set**(*obj*, *value*)

**rem**(*obj*, *params=None*)

**class** `pylablib.core.utils.functions.MethodObjectProperty(getter=None, setter=None, remover=None, expand_tuple=True)`

Bases: `IObjectProperty`

Object property created from object methods (makes methods look like properties).

**Parameters**

- **getter** (*callable*) – Method invoked on `get()`. If `None`, raise `RuntimeError` when called.
- **setter** (*callable*) – Method invoked on `set()`. If `None`, raise `RuntimeError` when called.
- **remover** (*callable*) – Method invoked on `rem()`. If `None`, raise `RuntimeError` when called.
- **expand\_tuple** (*bool*) – If `True` and if the first argument in the method call is a tuple, expand it as an argument list for the underlying function call.

**get**(*obj*, *params=None*)

**set**(*obj*, *value*)

**rem**(*obj*, *params=None*)

**class** `pylablib.core.utils.functions.AttrObjectProperty`(*name*, *use\_getter=True*, *use\_setter=True*,  
*use\_remover=True*, *expand\_tuple=True*)

Bases: `IObjectProperty`

Object property created from object attribute. Works with attributes or properties.

**Parameters**

- **name** (*str*) – Attribute name.
- **use\_getter** (*bool*) – If `False`, raise `RuntimeError` when calling `get` method.
- **use\_setter** (*bool*) – If `False`, raise `RuntimeError` when calling `set` method.
- **use\_remover** (*bool*) – If `False`, raise `RuntimeError` when calling `rem` method.
- **expand\_tuple** (*bool*) – If `True` and if the first argument in the method call is a tuple, expand it as an argument list for the underlying function call.

**get**(*obj*, *params=None*)

**set**(*obj*, *value*)

**rem**(*obj*, *params=None*)

`pylablib.core.utils.functions.empty_object_property`(*value=None*)

Dummy property which does nothing and returns *value* on `get` (`None` by default).

`pylablib.core.utils.functions.obj_prop`(\**args*, \*\**kwargs*)

Build an object property wrapper.

If no arguments (or a single `None` argument) are supplied, return a dummy property. If one argument is supplied, return `AttrObjectProperty` for a property with a given name. Otherwise, return `MethodObjectProperty` property.

`pylablib.core.utils.functions.as_obj_prop`(*value*)

Turn *value* into an object property using `obj_prop()` function.

If it's already `IObjectProperty`, return unchanged. If *value* is a tuple, expand as an argument list.

`pylablib.core.utils.functions.delaydef(gen)`

Wrapper for a delayed definition of a function inside of a module.

Useful if defining a function is computationally costly. The wrapped function should be a generator of the target function rather than the function itself.

On the first call the generator is executed to define the target function, which is then substituted for all subsequent calls.

## pylablib.core.utils.general module

Collection of small utilities.

`pylablib.core.utils.general.set_props(obj, prop_names, props)`

Set multiple attributes of *obj*.

Names are given by *prop\_names* list and values are given by *props* list.

`pylablib.core.utils.general.get_props(obj, prop_names)`

Get multiple attributes of *obj*.

Names are given by *prop\_names* list.

`pylablib.core.utils.general.getattr_multivar(obj, attrs, **kwargs)`

Try to get an attribute of *obj* given a list *attrs* of its potential names.

If no attributes are found and `default` keyword argument is supplied, return this default value; otherwise, raise `AttributeError`.

`pylablib.core.utils.general.using_method(func, method_name=None, inherit_signature=True)`

Decorator that makes the function attempt to call the first argument's method instead of *func*.

Before calling the function, try and call a method of the first argument named *method\_name* (*func* name by default). If the method exists, call it instead of the wrapped function. If *inherit\_signature*==True, completely copy the signature of the wrapped method (name, args list, docstring, etc.).

`pylablib.core.utils.general.to_predicate(x)`

Turn *x* into a predicate.

If *x* is callable, it will be called with a single argument and returned value determines if the argument passes. If *x* is a container, an argument passes if it's contained in *x*.

`pylablib.core.utils.general.map_container(value, func)`

Map values in the container.

*value* can be a tuple, a list or a dict (mapping is applied to the values) raises `ValueError` if it's something else.

`pylablib.core.utils.general.as_container(val, t)`

Turn iterable into a container of type *t*.

Can handle named tuples, which have different constructor signature.

`pylablib.core.utils.general.recursive_map(value, func)`

Map container recursively.

*value* can be a tuple, a list or a dict (mapping is applied to the values).

```
pylablib.core.utils.general.make_flat_namedtuple(nt, fields=None, name=None,  
                                                subfield_fmt='{field:}_{subfield:}')
```

Turn a nested structure of named tuples into a single flat namedtuple.

#### Parameters

- **nt** – toplevel namedtuple class to be flattened
- **fields** – a dictionary {**name**: **desc**} of the fields, where **name** is the named tuple name, and **desc** is either a nested namedtuple class, or a list of arguments which are passed to the recursive call to this function (e.g., [TTuple, {"field": TNestedTuple}]). Any tuple field which is present in this dictionary gets recursively flattened, and the field names of the corresponding returned tuple are added to the full list of fields
- **name** – name of the resulting tuple
- **subfield\_fmt** – format string, which describes how the combined field name is built out of the original field name and the subtree field name; by default, connect with "\_", i.e., `t.field.subfield` turns into `t.field_subfield`.

#### Returns

a new namedtuple class, which describes the flattened structure

```
pylablib.core.utils.general.any_item(d)
```

Return arbitrary tuple (**key**, **value**) contained in the dictionary (works both in Python 2 and 3)

```
pylablib.core.utils.general.merge_dicts(*dicts)
```

Combine multiple dict objects together.

If multiple dictionaries have the same keys, later arguments have higher priority.

```
pylablib.core.utils.general.filter_dict(pred, d, exclude=False)
```

Filter dictionary based on a predicate.

*pred* can be a callable or a container (in which case the predicate is true if a value is in the container). If *exclude==True*, the predicate is inverted.

```
pylablib.core.utils.general.map_dict_keys(func, d)
```

Map dictionary keys with *func*

```
pylablib.core.utils.general.map_dict_values(func, d)
```

Map dictionary values with *func*

```
pylablib.core.utils.general.to_dict(d, default=None)
```

Convert a dict or a list of pairs or single keys (or mixed) into a dict.

If a list element is single, *default* value is used.

```
pylablib.core.utils.general.to_pairs_list(d, default=None)
```

Convert a dict or a list of pairs or single keys (or mixed) into a list of pairs.

If a list element is single, *default* value is used. When converting list into list, the order is preserved.

```
pylablib.core.utils.general.invert_dict(d, kmap=None)
```

Invert dictionary (switch keys and values).

If *kmap* is supplied, it's a function mapping dictionary values into inverted dictionary keys (identity by default).

```
pylablib.core.utils.general.flatten_list(l)
```

Flatten nested list/tuple structure into a single list.

`pylablib.core.utils.general.partition_list(pred, l)`

Split the list `l` into two parts based on the predicate.

`pylablib.core.utils.general.split_in_groups(key_func, l, continuous=True, max_group_size=None)`

Split the list `l` into groups according to the `key_func`.

Go over the list and group the elements with the same key value together. If `continuous==False`, groups all elements with the same key together regardless of where they are in the list. otherwise, group only continuous sequences of the elements with the same key together (element with different key in the middle will result in two groups). If `continuous==True` and `max_group_size` is not `None`, it determines the maximal size of a group; larger groups are split into separate groups.

`pylablib.core.utils.general.sort_set_by_list(s, l, keep_duplicates=True)`

Convert the set `s` into a list ordered by a list `l`.

Elements in `s` which are not in `l` are omitted. If `keep_duplicates==True`, keep duplicate occurrences in `l` in the result; otherwise, only keep the first occurrence.

`pylablib.core.utils.general.compare_lists(l1, l2, sort_lists=False, keep_duplicates=True)`

Return three lists (`l1` and `l2`, `l1-l2`, `l2-l1`).

If `sort_lists==True`, sort the first two lists by `l1`, and the last one by `l2`; otherwise, the order is undefined. If `sort_lists==True`, `keep_duplicated` determines if duplicate elements show up in the result.

`pylablib.core.utils.general.topological_order(graph, visit_order=None)`

Get a topological order of a graph.

Return a list of nodes where each node is listed after its children. If `visit_order` is not `None`, it is a list specifying nodes visiting order (nodes earlier in the list are visited first). Otherwise, the visit order is undefined. `graph` is a dictionary `{node: [children]}`. If graph contains loops, raise `ValueError`.

**class** `pylablib.core.utils.general.DummyResource`

Bases: `object`

Object that acts as a resource (has `__enter__` and `__exit__` methods), but doesn't do anything.

Analog of:

```
@contextlib.contextmanager
def dummy_resource():
    yield
```

`pylablib.core.utils.general.unique_class(repr_text='UNIQUE')`

Return a newly created unique class with the given representation text.

Can be used as a placeholder in methods where a “not supplied” default value is required, but any value can in principle be supplied.

**class** `pylablib.core.utils.general.RetryOnException(tries=None, exceptions=None)`

Bases: `object`

Wrapper for repeating the same block of code several time if an exception occurs

Useful for filesystem or communication operations, where retrying a failed operation is a valid option.

#### Parameters

- **tries** (`int`) – Determines how many time will the chunk of code execute before re-raising the exception; `None` (default) means no limit

- **exceptions** (*Exception* or *list*) – A single exception class or a list of exception classes which are going to be silenced.

Example:

```
for t in RetryOnException(tries, exceptions):
    with t:
        ... do stuff ...
```

is analogue of:

```
for i in range(tries):
    try:
        ... do stuff ...
    except exceptions:
        if i==tries-1:
            raise
```

```
class ExceptionCatcher(retrier, try_number)
```

Bases: *object*

**reraise()**

`pylablib.core.utils.general.retry_wait(func, try_times=1, delay=0.0, exceptions=None)`

Try calling function (with no arguments) at most *try\_times* as long as it keeps raising exception.

If *exceptions* is not *None*, it specifies which exception types should be silenced. If an exception has been raised, wait *delay* seconds before retrying.

```
class pylablib.core.utils.general.SilenceException(exceptions=None, on_exception=None,
                                                    reraise=False)
```

Bases: *object*

Context which silences exceptions raised in a block of code.

#### Parameters

- **exceptions** (*Exception* or *list*) – A single exception class or a list of exception classes which are going to be silenced.
- **on\_exception** (*callable*) – A callback to be invoked if an exception occurs.
- **reraise** (*bool*) – Defines if the exception is re-raised after the callback has been invoked.

A simple bit of syntax sugar. The code:

```
with SilenceException(exceptions, on_exception, reraise):
    ... do stuff ...
```

is exactly analogous to:

```
try:
    ... do stuff ...
except exceptions:
    on_exception()
    if reraise:
        raise
```



`pylablib.core.utils.general.full_exit(code=Signals.SIGTERM)`

Terminate the current process and all of its threads.

Doesn't perform any cleanup or resource release; should only be used if the process is irrevocably damaged.

**class** `pylablib.core.utils.general.UIDGenerator(thread_safe=False)`

Bases: `object`

Generator of unique numeric IDs.

#### Parameters

**thread\_safe** (*bool*) – If `True`, using lock to ensure that simultaneous calls from different threads are handled properly.

**reset**(*value=0*)

Reset the generator to the given value

**class** `pylablib.core.utils.general.NamedUIDGenerator(name_template='{0}{1:03d}', thread_safe=False)`

Bases: `object`

Generator of unique string IDs based on a name.

#### Parameters

- **name\_template** (*str*) – Format string with two parameters (name and numeric ID) used to generate string IDs.
- **thread\_safe** (*bool*) – If `True`, using lock to ensure that simultaneous calls from different threads are handled properly.

`pylablib.core.utils.general.call_limit(func, period=1, cooldown=0.0, limit=None, default=None)`

Wrap *func* such that calls to it are forwarded only under certain conditions.

If `period>1`, then *func* is called after at least *period* calls to the wrapped function. If `cooldown>0`, then *func* is called after at least *cooldown* seconds passed since the last call. if `limit` is not `None`, then *func* is called only first *limit* times. If several conditions are specified, they should be satisfied simultaneously. *default* specifies return value if *func* wasn't called. Returned function also has an added method `reset`, which resets the internal call and time counters.

`pylablib.core.utils.general.doc_inherit(parent)`

Wrapper for inheriting docstrings from parent classes.

Takes parent class as an argument and replaces the docstring of the wrapped function by the docstring of the same-named function from the parent class (if available).

**class** `pylablib.core.utils.general.Countdown(timeout, start=True)`

Bases: `object`

Object for convenient handling of timeouts and countdowns with interrupts.

#### Parameters

- **timeout** (*float*) – Countdown timeout; if `None`, assumed to be infinite.
- **start** (*bool*) – if `True`, automatically start the countdown; otherwise, wait until `trigger()` is called explicitly

**reset**(*start=True*)

Restart the countdown from the current moment

**trigger**(*restart=True*)

Trigger the countdown.

If *restart==True*, restart the countdown if it's running; otherwise, do nothing in that situation.

**running**()

Check if the countdown is running

**stop**()

Stop the timer if currently running

**time\_left**(*t=None, bound\_below=True*)

Return the amount of time left. For infinite timeout, return *None*.

If *bound\_below==True*, instead of negative time return zero. If *t* is supplied, it indicates the current time; otherwise, use *time.time()*.

**add\_time**(*dt, t=None, bound\_below=True*)

Add a given amount of time (positive or negative) to the start time (timeout stays the same).

If *bound\_below==True*, do not let the end time (start time plus timeout) to get below the current time. If *t* is supplied, it indicates the current time; otherwise, use *time.time()*.

**set\_timeout**(*timeout*)

Change the timer timeout

**time\_passed**()

Return the amount of time passed since the countdown start/reset, or *None* if it is not started

**passed**()

Check if the timeout has passed

**class** `pylablib.core.utils.general.Timer`(*period, skip\_first=False*)

Bases: `object`

Object for keeping time of repeating tasks.

**Parameters**

**period** (*float*) – Timer period.

**change\_period**(*period, method='current'*)

Change the timer period.

*method* specifies the changing method. Could be "current" (change the period of the ongoing tick), "next" (change the period starting from the next tick), "reset\_skip" (reset the timer and skip the first tick) or "reset\_noskip" (reset the timer and don't skip the first tick).

**reset**(*skip\_first=False*)

Reset the timer.

If *skip\_first==False*, timer ticks immediately; otherwise, it starts ticking only after one period.

**time\_left**(*t=None, bound\_below=True*)

Return the amount of time left before the next tick.

If *bound\_below==True*, instead of negative time return zero.

**passed**(*t=None*)

Return the number of ticks passed.

If timer period is zero, always return 1.

**acknowledge**(*n=None, nmin=0*)

Acknowledge the timer tick.

*n* specifies the number of tick to acknowledge (by default, all passed). Return number of actually acknowledged ticks (0 if the timer hasn't ticked since the last acknowledgement).

**class** `pylablib.core.utils.general.TimeTracker(verbose='all')`

Bases: `object`

Time tracker used for estimating time for different sections of code.

#### Parameters

**verbose** – determines the verbosity level; can be "all" (print on mark and on summary), "summary" (only print summery), or "none" (do not print anything)

**reset**()

Reset the internal timer

**summary**(*join\_records='auto', exclude\_untracked=True, compact=False, reset=True, period=None*)

Print the sections runtime summary.

If `join_records==True`, count all records with the same message as the same event and present total / per call statistics; otherwise, print one line per record. If `join_records=="auto"`, set to `True` if there are several records with the same name. If `exclude_untracked==True`, exclude code periods marked with no message (i.e., `None`) from the total time calculation. If `compact==True`, only print one line per record; otherwise, also include header and total time. If `reset==True`, reset the sections history. If *period* is not `None`, defines the maximal summary printing period.

**class** `pylablib.core.utils.general.StreamFileLogger(path, stream=None, lock=None, autoflush=False)`

Bases: `object`

Stream logger that replaces standard output stream (usually `stdout` or `stderr`) and logs them into a file.

#### Parameters

- **path** – path to the destination logfile. The file is always appended.
- **stream** – an optional output stream into which the output will be duplicated; usually, the original stream which is being replaced
- **lock** – a thread lock object, which is used for any file writing operation; necessary if replacing standard streams (such as `sys.stdout` or `sys.stderr`) in a multithreading environment.
- **autoflush** – if `True`, flush after any write operation into *stream*

It is also possible to subclass the file and overload `write_header()` method to write a header before the first file write operation during the execution.

The intended use is to log `stdout` or `stderr` streams:

```
import sys, threading
sys.stderr = StreamFileLogger("error_log.txt", stream=sys.stderr, lock=threading.
↳ Lock())
```

**write\_header**(*f*)

Write header to file stream *f*

**add\_path**(*path*)

Add another logging path to the list

**add\_stream**(*stream*)

Add another output stream to the list

**remove\_path**(*path*)

Remove logging path to the list

**write**(*s*)

**flush**()

`pylablib.core.utils.general.setbp()`

`pylablib.core.utils.general.timing(n=1, name=None, profile=False)`

Context manager for timing a piece of code.

Measures the time it takes to execute the wrapped code and prints the result.

#### Parameters

- **n** – can specify the number of repetitions, which is used to show time per single repetition.
- **name** – name which is printed alongside the time
- **profile** – if True, use cProfile and print its output instead of a simple timing

**class** `pylablib.core.utils.general.AccessIterator(obj, access_function=None)`

Bases: `object`

Simple sequential access iterator with customizable access function (by default it's 1D indexing).

Determines end of iterations by `IndexError`.

#### Parameters

- **obj** – Container to be iterated over.
- **access\_function** (*callable*) – A function which takes two parameters *obj* and *idx* and either returns the element or raises `IndexError`. By default, a simple `__getitem__` operation.

**next**()

`pylablib.core.utils.general.muxcall(argname, special_args=None, mux_argnames=None, return_kind='list', allow_partial=False)`

Wrap a function such that it can become multiplexable over a given argument.

#### Parameters

- **argname** – name of the argument to loop over
- **special\_args** – if not None, defines a dictionary {*arg*: *func*} for special values of the argument (e.g., "all", None, etc.), where *arg* is its value, and *func* is the method taking the same arguments as the called function and returning the substitute argument (e.g., a list of all arguments)
- **mux\_argnames** – names of additional arguments which, when supplied list or dict values, and when the *argname* value is a list, specify different values for different calls
- **return\_kind** – method to combined multiple returned values; can be "list", "dict" (return dict {*arg*: *result*}), or "none" (simply return None)
- **allow\_partial** – if True and some of *mux\_argnames* argument do not specify value for the full range of *argname* value, do not call the function for those unspecified values; otherwise (*allow\_partial* is False), the error will be raised

`pylablib.core.utils.general.wait_for_keypress(message='Waiting...')`

`pylablib.core.utils.general.restart()`

Restart the script.

Execution will not resume after this call. Note: due to Windows limitations, this function does not replace the current process with a new one, but rather calls a new process and makes the current one wait for its execution. Hence, each nested call adds an additional loaded application into the memory. Therefore, nesting restart calls (i.e., calling several restarts in a row) should be avoided.

## pylablib.core.utils.indexing module

Processing and normalization of different indexing styles.

`pylablib.core.utils.indexing.string_list_idx(names_to_find, names_list, only_exact=False)`

Index through a list of strings in *names\_list*.

Return corresponding numerical indices. Case sensitive; first look for exact matching, then for prefix matching (unless `only_exact=True`).

`pylablib.core.utils.indexing.is_slice(idx)`

Check if *idx* is slice.

`pylablib.core.utils.indexing.is_range(idx)`

Check if *idx* is iterable (list, numpy array, or *builtins.range*).

`pylablib.core.utils.indexing.is_bool_array(idx)`

Check if *idx* is a boolean array.

`pylablib.core.utils.indexing.to_range(idx, length)`

Turn list, array, *builtins.range*, slice into an iterable.

`pylablib.core.utils.indexing.covers_all(idx, length, strict=False, ordered=True)`

Check if *idx* covers all of the elements (indices from 0 to *length*).

If `strict==True`, strictly checks the condition; otherwise may return `False` even if *idx* actually covers everything, but takes less time (i.e., can be used for optimization). If `ordered==True`, only returns `True` when indices follow in order.

**class** `pylablib.core.utils.indexing.IIndex`

Bases: `object`

A generic index object.

Used to transform a variety of indexes into a subset applicable for specific objects (numpy arrays or lists).

**Allowed input index types:**

- scalar: integer, string
- vector: integer lists or numpy arrays, bool lists or numpy arrays, string lists or numpy arrays, *builtin.ranges*, slices and string slices

**tup()**

Represent index as a tuple for easy unpacking.

**class** pylablib.core.utils.indexing.**NumpyIndex**(*idx*, *ndim=None*)

Bases: [\*IIndex\*](#)

NumPy compatible index: allows for integers, slices, numpy integer or boolean arrays, integer lists or builtin.ranges.

**Parameters**

- **idx** – raw index
- **ndim** – index dimensionality (either 0 or 1); if supplied, assume that *idx* is already normalized

**tup()**

Represent index as a tuple for easy unpacking.

**class** pylablib.core.utils.indexing.**ListIndex**(*idx*, *names=None*, *ndim=None*)

Bases: [\*IIndex\*](#)

List compatible index: allows for integers, slices, numpy integer arrays, integer lists or builtin.ranges.

**Parameters**

- **idx** – raw index
- **names** – list of allowed index string values, which is used to convert them into integers
- **ndim** – index dimensionality (either 0 or 1); if supplied, assume that *idx* is already normalized

**tup()**

Represent index as a tuple for easy unpacking.

**class** pylablib.core.utils.indexing.**ListIndexNoSlice**(*idx*, *names=None*, *length=None*, *ndim=None*)

Bases: [\*ListIndex\*](#)

List compatible index with slice unwrapped into builtin.range: allows for integers, numpy integer arrays, integer lists or builtin.ranges.

**Parameters**

- **idx** – raw index
- **names** – list of allowed index string values, which is used to convert them into integers
- **length** – length of the list (used to expand slice indices)
- **ndim** – index dimensionality (either 0 or 1); if supplied, assume that *idx* is already normalized

**tup()**

Represent index as a tuple for easy unpacking.

pylablib.core.utils.indexing.**to\_double\_index**(*idx*, *names*)

Convert double index into a pair of indexes.

Assume that one index is purely numerical, while the other can take names (out of the supplied list).

**Parameters**

- **idx** – raw double index
- **names** – list of allowed index string values, which is used to convert them into integers

## pylablib.core.utils.ipc module

Universal interface for inter-process communication.

Focus on higher throughput for large numpy arrays via shared memory.

**class** `pylablib.core.utils.ipc.IIPCChannel`

Bases: `object`

Generic IPC channel interface

**send**(*data*)

Send data

**recv**(*timeout=None*)

Receive data

**send\_numpy**(*data*)

Send numpy array

**recv\_numpy**(*timeout=None*)

Receive numpy array

**get\_peer\_args**()

Get arguments required to create a peer connection

**classmethod from\_args**(\**args*)

Create a peer connection from the supplied arguments

**class** `pylablib.core.utils.ipc.TPipeMsg(id, data)`

Bases: `tuple`

**data**

**id**

**class** `pylablib.core.utils.ipc.PipeIPCChannel(pipe_conn=None)`

Bases: `IIPCChannel`

Generic IPC channel interface using pipe.

**get\_peer\_args**()

Get arguments required to create a peer connection

**send**(*data*)

Send data

**recv**(*timeout=None*)

Receive data

**classmethod from\_args**(\**args*)

Create a peer connection from the supplied arguments

**recv\_numpy**(*timeout=None*)

Receive numpy array

**send\_numpy**(*data*)

Send numpy array

```
class pylablib.core.utils.ipc.SharedMemIPCChannel(pipe_conn=None, arr=None, arr_size=None)
```

Bases: [PipeIPCChannel](#)

Generic IPC channel interface using pipe and shared memory for large arrays.

```
get_peer_args()
```

Get arguments required to create a peer connection

```
send_numpy(data, method='auto', timeout=None)
```

Send numpy array

```
recv_numpy(timeout=None)
```

Receive numpy array

```
classmethod from_args(*args)
```

Create a peer connection from the supplied arguments

```
recv(timeout=None)
```

Receive data

```
send(data)
```

Send data

```
class pylablib.core.utils.ipc.TShmemVarDesc(offset, size, kind, fixed_size)
```

Bases: [tuple](#)

**fixed\_size**

**kind**

**offset**

**size**

```
class pylablib.core.utils.ipc.SharedMemIPCTable(pipe_conn=None, arr=None, arr_size=None,  
                                              lock=True)
```

Bases: [object](#)

Shared memory table for exchanging shared variables between processes.

Can be used instead of channels for variables which are rarely changed but frequently checked (e.g., status), or when synchronization of sending and receiving might be difficult

```
add_variable(name, size, kind='pickle')
```

Add a variable with a given name.

The variable info is also communicated to the other endpoint. *size* determines maximal variable size in bytes. If the actual size ever exceeds it, an exception will be raised. *kind* determines the way to convert variable into bytes; can be "pickle" (universal, but large size overhead), "nps\_###" (where ### can be any numpy scalar dtype description, e.g., "float" or "<u2") for numpy scalars, or "npa\_###" (where ### means the same as for nps) for numpy arrays (in this case the array size and shape need to be communicated separately).

```
set_variable(name, value)
```

Set a variable with a given name.

If the variable is missing, raise an exception.



**get\_variable**(*name*, *default=None*)

Get a variable with a given name.

If the variable is missing, return *default*.

**is\_peer\_connected**()

Check if the peer is connected (i.e., the other side of the pipe is initialized)

**close\_connection**()

Mark the connection as closed

**is\_peer\_closed**()

Check if the peer is closed

**get\_peer\_args**()

Get arguments required to create a peer connection

**classmethod from\_args**(\**args*)

Create a peer connection from the supplied arguments

## pylablib.core.utils.library\_parameters module

Storage for global library parameters

**pylablib.core.utils.library\_parameters.temp\_library\_parameters**(*restore=None*)

Context manager, which restores library parameters upon exit.

If *rester* is not *None*, it can specify a list of parameters to be restored (by default, all parameters).

## pylablib.core.utils.module module

Library for dealing with python module properties.

**pylablib.core.utils.module.get\_package\_version**(*pkg*)

Get the version of the package.

If the package version is unavailable, return *None*.

**pylablib.core.utils.module.cmp\_versions**(*ver1*, *ver2*, *default='?'*)

Compare two package versions.

Return '<' if the first version is older (smaller), '>' if it's younger (larger) or '=' if it's the same. If the versions are not comparable (e.g., have different format), return *default*.

**pylablib.core.utils.module.cmp\_package\_version**(*pkg*, *ver*)

Compare current package version to *ver*.

*ver* should be a name of the package (rather than the module). Return '<' if current version is older (smaller), '>' if it's younger (larger) or '=' if it's the same. If the package version is unavailable, return *None*.

**pylablib.core.utils.module.expand\_relative\_path**(*module\_name*, *rel\_path*)

Turn a relative module path into an absolute one.

*module\_name* is the absolute name of the reference module, *rel\_path* is the path relative to this module.

`pylablib.core.utils.module.get_loaded_package_modules(pkg_name)`

Get all modules in the package *pkg\_name*.

Returns a dict {name: module}.

`pylablib.core.utils.module.get_imported_modules(module, explicit=False)`

Get modules imported within a given module.

If `explicit==True`, take into account only toplevel objects which are modules (corresponds to `import module` or `from package import module` statements) If `explicit==False`, also include all modules containing toplevel objects (corresponds to `from module import Class` or `from package import function` statements). Return a dictionary {name: module} (modules with the same name are considered to be the same).

`pylablib.core.utils.module.get_reload_order(modules)`

Find reload order for modules which respects dependencies (a module is loaded before its dependents).

*modules* is a dict {name: module}.

The module dependencies (i.e., the modules which the current module depends on) are determined based on imported modules and modules containing toplevel module objects.

`pylablib.core.utils.module.reload_package_modules(pkg_name, ignore_errors=False)`

Reload package *pkg\_name*, while respecting dependencies of its submodules.

If `ignore_errors=True`, ignore `ImportError` exceptions during the reloading process.

`pylablib.core.utils.module.unload_package_modules(pkg_name, ignore_errors=False)`

Reload package *pkg\_name*, while respecting dependencies of its submodules.

If `ignore_errors=True`, ignore `ImportError` exceptions during the reloading process.

`pylablib.core.utils.module.get_library_path()`

Get a filesystem path for the pyLabLib library (the one containing current the module).

`pylablib.core.utils.module.get_library_name()`

Get the name for the pyLabLib library (the one containing current the module).

`pylablib.core.utils.module.get_executable(console=False)`

Get Python executable.

If `console==True` and the current executable is windowed (i.e., "pythonw.exe"), return the corresponding "python.exe" instead.

`pylablib.core.utils.module.get_python_folder()`

Return Python interpreter folder (the folder containing the python executable)

`pylablib.core.utils.module.pip_install(pkg, upgrade=False)`

Call `pip install` for a given package.

If `upgrade==True`, call with `--upgrade` key (upgrade current version if it is already installed).

`pylablib.core.utils.module.install_if_older(pkg, min_ver="")`

Install *pkg* from the default PyPI repository if its version is lower that *min\_ver*

If *min\_ver* is None, upgrade to the newest version regardless; if *min\_ver==""*, install only if no version is installed. Return True if the package was installed.

**pylablib.core.utils.nbtools module**

`pylablib.core.utils.nbtools.c_array(base='u1', ndim=1, readonly=False, contiguous='C')`

Generate a numba C-ordered array type with the given element type, number of dimensions, and read-only and contiguous flags

`pylablib.core.utils.nbtools.au1(x, off)`

Extract a little-endian 1-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.au2(x, off)`

Extract a little-endian 2-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.au4(x, off)`

Extract a little-endian 4-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.au8(x, off)`

Extract a little-endian 8-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.ai1(x, off)`

Extract a little-endian 1-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.ai2(x, off)`

Extract a little-endian 2-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.ai4(x, off)`

Extract a little-endian 4-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.ai8(x, off)`

Extract a little-endian 8-byte unsigned integer from a numpy byte array at the given offset

`pylablib.core.utils.nbtools.copy_array_chunks(base='u1', par=False, nogil=True)`

Generate and compile a numba function for copying an array in chunks. *base* specifies the base array type (by default, unsigned byte); if *par*==True, generate a parallelized implementation. if *nogil*==True, use the *nogil* numba option to release GIL during the execution.

The returned function takes 4 arguments: source array, destination array, number of chunks, and size (in elements) of each chunk.

`pylablib.core.utils.nbtools.copy_array_strided(base='u1', par=False, nogil=True)`

Generate and compile a numba function for copying an array in chunks with an arbitrary stride. *base* specifies the base array type (by default, unsigned byte); if *par*==True, generate a parallelized implementation. if *nogil*==True, use the *nogil* numba option to release GIL during the execution.

The returned function takes 6 arguments: source array, destination array, number of chunks, size (in elements) of each chunk, chunks stride (in elements) in the source array, and offset (in elements) from the beginning of the first array. If size is the same as stride and the offset is zero, this function would mimic the one generated by [`copy\_array\_chunks\(\)`](#).

**pylablib.core.utils.net module**

A wrapper for built-in TCP/IP routines.

**exception** `pylablib.core.utils.net.SocketError`

Bases: `OSError`

Base socket error class.

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****characters\_written****errno**

POSIX exception code

**filename**

exception filename

**filename2**

second exception filename

**strerror**

exception strerror

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.core.utils.net.SocketTimeout`

Bases: `SocketError`

Socket timeout error.

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****characters\_written****errno**

POSIX exception code

**filename**

exception filename

**filename2**

second exception filename

**strerror**

exception strerror

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

`pylablib.core.utils.net.get_local_addr()`

Get local IP address

`pylablib.core.utils.net.get_all_local_addr()`

Get a list of all local IP addresses

`pylablib.core.utils.net.get_local_hostname(full=True)`

Get a local host name

`pylablib.core.utils.net.get_all_remote_addr(hostname)`

Get a list of all remote addresses of a remote host by name

`pylablib.core.utils.net.get_remote_hostname(addr, error_on_missing=False)`

Get a remote host name by its address

`pylablib.core.utils.net.as_addr_port(addr, port)`

Parse the given address and port combination.

*addr* can be a host address, a tuple (*addr*, *port*), or a string "*addr:port*"; in the first case the given *port* is used, while in the other two it is ignore. Return tuple (*addr*, *port*).

**class** `pylablib.core.utils.net.ClientSocket(sock=None, timeout=None, wait_callback=None, send_method='declen', recv_method='declen', datatype='auto', nodelay=False)`

Bases: `object`

A client socket (used to connect to a server socket).

#### Parameters

- **sock** (`socket.socket`) – Socket to wrap; if `None` create a new one.
- **timeout** (`float`) – The timeout used for connecting and sending/receiving (`None` means no timeout).
- **wait\_callback** (`callable`) – Called periodically (every 100ms by default) while waiting for connecting or sending/receiving.
- **send\_method** (`str`) – Default sending method.
- **recv\_method** (`str`) – Default receiving method.
- **datatype** (`str`) – Type of the returned data; can be "bytes" (return *bytes* object), "str" (return *str* object), or "auto" (default Python result: *str* in Python 2 and *bytes* in Python 3)
- **nodelay** (`bool`) – Whether to enable TCP\_NODELAY.

#### Possible sending/receiving methods are:

- 'fixedlen': data is sent as is, and receiving requires to know the length of the message;
- 'declen': data is prepended by a length, and receiving reads this length and doesn't need pre-terminated length info.

#### sock

Corresponding Python socket.

#### Type

`socket.socket`

**decllen\_bo**

Byteorder of the prepended length for 'decllen' sending method. Can be either '>' (big-endian, default) or '<'.

**Type**

str

**decllen\_ll**

Length of the prepended length for 'decllen' sending method; default is 4 bytes (corresponding to maximum of 4Gb per single length-prepended message)

**Type**

int

**set\_wait\_callback**(wait\_callback=None)

Set callback function for waiting during connecting or sending/receiving

**set\_timeout**(timeout=None)

Set timeout for connecting or sending/receiving

**get\_timeout**()

Get timeout for connecting or sending/receiving

**using\_timeout**(timeout=None)

Context manager for usage of a different timeout inside a block

**connect**(host, port)

Connect to a remote host

**close**()

Close the connection

**is\_connected**()

Check if the connection is opened

**get\_local\_name**()

Return IP address and port of this socket

**get\_peer\_name**()

Return IP address and port of the peer socket

**recv\_fixedlen**(l)

Receive fixed-length message of length *l*

**recv\_delimiter**(delim, lmax=None, chunk\_l=1024, strict=False)

Receive a single message ending with a delimiter *delim* (can be several characters, or list several possible delimiter strings).

*lmax* specifies the maximal received length (*None* means no limit). *chunk\_l* specifies the size of data chunk to be read in one try. If *strict*==False, keep receiving as much data as possible until a delimiter is found in the end (only works properly if a single line is expected); otherwise, receive the data byte-by-byte and stop as soon as a delimiter is found (equivalent to setting *chunk\_l*=1).

**recv\_decllen**()

Receive variable-length message (prepended by its length).

Length format is described by *decllen\_bo* and *decllen\_ll* attributes.

**recv**(*l=None*)

Receive a message using the default method.

**recv\_all**(*chunk\_l=1024*)

Receive all of the data currently in the socket.

*chunk\_l* specifies the size of data chunk to be read in one try. For technical reasons, use 1ms timeout (i.e., this operation takes 1ms).

**recv\_ack**(*l=None*)

Receive a message using the default method and send an acknowledgement (message length)

**send\_fixedlen**(*msg*)

Send a message as is

**send\_decllen**(*msg*)

Send a message as a variable-length (prepending its length in the sent message).

Length format is described by *declen\_bo* and *declen\_ll* attributes.

**send\_delimiter**(*msg, delimiter*)

Send a message with a delimiter *delim* (can be several characters)

**send**(*msg*)

Send a message using the default method.

**send\_ack**(*msg*)

Send a message using default method and wait for acknowledgement (message length).

If the acknowledgement message length doesn't agree, raise [SocketError](#).

`pylablib.core.utils.net.recv_JSON(sock, chunk_l=1024, strict=True)`

Receive a complete JSON token from the socket.

*chunk\_l* specifies the size of data chunk to be read in one try. If `strict==False`, keep receiving as much data as possible until the received data forms a complete JSON token. otherwise, receive the data byte-by-byte and stop as soon as a token is formed (equivalent to setting `chunk_l=1`).

`pylablib.core.utils.net.listen(host, port, conn_func, port_func=None, wait_callback=None, timeout=None, backlog=10, wrap_socket=True, connections_number=None, socket_kwargs=None)`

Run a server socket at the given host and port.

#### Parameters

- **host** (*str*) – Server host address. If `None`, use the local host defined by `socket.gethostname()`.
- **port** (*int*) – Server port. If `0`, generate an arbitrary free port.
- **conn\_func** (*callable*) – Called with the client socket as a single argument every time a connection is established.
- **port\_func** (*callable*) – Called with the port as a single argument when the listening starts (useful with `port=0`).
- **wait\_callback** (*callable*) – A callback function which is called periodically (every 100ms by default) while awaiting for connections.
- **timeout** (*float*) – Timeout for waiting for the connections (`None` is no timeout).
- **backlog** (*int*) – Backlog length for the socket (see `socket.socket.listen()`).

- **wrap\_socket** (*bool*) – If True, wrap the client socket of the connection into `ClientSocket` class; otherwise, return `socket.socket` object.
- **connections\_number** (*int*) – Specifies maximal number of connections before the listening function returns (by default, the number is unlimited).
- **socket\_kwargs** (*dict*) – additional keyword arguments passed to `ClientSocket` constructor.

Checking for connections is paused until `conn_func` returns. If multiple simultaneous connections are expected, `conn_func` should spawn a separate processing thread and return. If `connections_number` is None (i.e., there's no limit on the number of connections before closing), this function never returns.

## pylablib.core.utils.numerical module

Numerical functions that don't deal with sequences.

`pylablib.core.utils.numerical.gcd(*numbers)`

Euclid's algorithm for GCD. Arguments are cast to integer

`pylablib.core.utils.numerical.integer_distance(x)`

Get distance to the closes integer

`pylablib.core.utils.numerical.gcd_approx(a, b, min_fraction=1e-08, tolerance=1e-05)`

Approximate Euclid's algorithm for possible non-integer values.

Try to find a number  $d$  such that  $a/d$  and  $b/d$  are less than *tolerance* away from a closest integer. If GCD becomes less than `min_fraction * min(a, b)`, raise `ArithmeticError`.

`pylablib.core.utils.numerical.round_significant(x, n)`

Rounds  $x$  to  $n$  significant digits (not the same as  $n$  decimal places!).

`pylablib.core.utils.numerical.limit_to_range(x, min_val=None, max_val=None, default=0)`

Confine  $x$  to the given limit.

Default limit values are None, which means no limit. *default* specifies returned value if both  $x$ , *min\_val* and *max\_val* are None.

**class** `pylablib.core.utils.numerical.infinite_list(start=0, step=1)`

Bases: `object`

Mimics the behavior of the usual list, but is infinite and immutable.

Supports accessing elements, slicing (including slices giving infinite lists) and iterating. Iterating over it naturally leads to an infinite loop, so it should only be used either for finite slices or for loops with break condition.

### Parameters

- **start** – The first element of the list.
- **step** – List step.

**class** `counter(lst)`

Bases: `object`

**next()**

`pylablib.core.utils.numerical.unity()`

Return a unity function



`pylablib.core.utils.numerical.constant(c)`

Return a function which returns a constant *c*.

*c* can only be either a scalar, or an array-like object with the shape matching the expected argument.

`pylablib.core.utils.numerical.polynomial(coeffs)`

Return a polynomial function which with coefficients *coeffs*.

Coefficients are list lowest-order first, so that `coeffs[i]` is the coefficient in front of  $x^{**i}$ .

## pylablib.core.utils.observer\_pool module

A simple observer pool (notification pool) implementation.

**class** `pylablib.core.utils.observer_pool.ObserverPool(expand_tuple=True)`

Bases: `object`

An observer pool.

Stores notification functions (callbacks), and calls them whenever `notify()` is called. The callbacks can have priority (higher priority ones are called first) and filter (observer is only called if the filter function passes the notification tag).

### Parameters

**expand\_tuple** (*bool*) – if `True` and the notification value is a tuple, treat it as an argument list for the callback functions.

**class** `Observer(filt, callback, priority, attr, cacheable)`

Bases: `tuple`

**attr**

**cacheable**

**callback**

**filt**

**priority**

**add\_observer**(*callback, name=None, filt=None, priority=0, attr=None, cacheable=False*)

Add the observer callback.

### Parameters

- **callback** (*callable*) – callback function; takes at least one argument (notification tag), and possible more depending on the notification value.
- **name** (*str*) – stored callback name; by default, a unique name is auto-generated
- **filt** (*callable or None*) – a filter function for this observer (the observer is called only if the `notify()` function tag and value pass the filter); by default, all tags are accepted
- **priority** (*int*) – callback priority; higher priority callback are invoked first.
- **attr** – additional observer attributes (can be used by `ObserverPool` subclasses to change their behavior).
- **cacheable** (*bool*) – if `True`, assumes that the filter function only depends on the tag, so its calls can be cached.

**Returns**

callback name (equal to *name* if supplied; an automatically generated name otherwise).

**remove\_observer**(*name*)

Remove the observer callback with the given name

**find\_observers**(*tag*, *value*)

**notify**(*tag*, *value*=())

Notify the observers by calling their callbacks.

Return a dictionary of the callback results. By default the value is an empty tuple: for `expand_tuple==True` this means that only one argument (*tag*) is passed to the callbacks.

**pylablib.core.utils.py3 module**

Dealing with Python2 / Python3 compatibility.

**pylablib.core.utils.py3.as\_str**(*data*)

Convert a string into a text string

**pylablib.core.utils.py3.as\_bytes**(*data*)

Convert a string into bytes

**pylablib.core.utils.py3.as\_builtin\_bytes**(*data*)

Convert a string into bytes

**pylablib.core.utils.py3.as\_datatype**(*data*, *datatype*)

Convert a string into a given datatypes.

*datatype* can be "str" (text string), "bytes" (byte string), or "auto" (no conversion).

**pylablib.core.utils.rpyc\_utils module**

Routines and classes related to RPyC package

**pylablib.core.utils.rpyc\_utils.obtain**(*proxy*, *serv*=None, *deep*=False, *direct*=False)

Obtain a remote netref object by value (i.e., copy it to the local Python instance).

Wrapper around `rpyc.utils.classic.obtain()` with some special cases handling. *serv* specifies the current remote service. If it is of type `SocketTunnelService`, use its socket tunnel for faster transfer. If `deep==True` and *proxy* is a container (tuple, list, or dict), run the function recursively for all its sub-elements. If `direct==True`, directly use RPyC obtain method; otherwise use the custom method, which works better with large numpy arrays, but worse with composite types (e.g., lists).

**pylablib.core.utils.rpyc\_utils.transfer**(*obj*, *serv*)

Send a local object to the remote PC by value (i.e., copy it to the remote Python instance).

A 'reversed' version of `obtain()`.

**class** `pylablib.core.utils.rpyc_utils.SocketTunnelService`(\*args: Any, \*\*kwargs: Any)

Bases: `SlaveService`

Extension of the standard `rpyc.core.service.SlaveService` with built-in network socket tunnel for faster data transfer.

In order for the tunnel to work, services on both ends need to be subclasses of `SocketTunnelService`. Because of the initial setup protocol, the two services are asymmetric: one should be 'server' (corresponding to the

listening server), and one should be ‘client’ (external connection). The roles are decided by the *server* constructor parameter.

**tunnel\_send**(*obj*, *packer*=None)

Send data through the socket tunnel.

If *packer* is not None, it defines a function to convert *obj* to a bytes string.

**tunnel\_recv**(*unpacker*=None)

Receive data sent through the socket tunnel.

If *unpacker* is not None, it defines a function to convert the received bytes string into an object.

**obtain**(*proxy*)

Execute *obtain()* on the local instance

**transfer**(*obj*)

Execute *transfer()* on the local instance

**on\_connect**(*conn*)

**on\_disconnect**(*conn*)

**class** `pylablib.core.utils.rpyc_utils.DeviceService(*args: Any, **kwargs: Any)`

Bases: *SocketTunnelService*

Device RPyC service.

Expands on *SocketTunnelService* by adding *get\_device()* method, which opens local devices, tracks them, and closes them automatically on disconnect.

**on\_connect**(*conn*)

**on\_disconnect**(*conn*)

**get\_device\_class**(*cls*)

Get remote device class.

*cls* is the full class name, including the module within `pylablib.devices` (e.g., `Attocube.ANC300`).

**get\_device**(*cls*, \*args, \*\*kwargs)

Connect to a device.

*cls* is the full class name, including the module within `pylablib.devices` (e.g., `Attocube.ANC300`). Stores reference to the connected device and closes it automatically on disconnect.

**obtain**(*proxy*)

Execute *obtain()* on the local instance

**transfer**(*obj*)

Execute *transfer()* on the local instance

**tunnel\_recv**(*unpacker*=None)

Receive data sent through the socket tunnel.

If *unpacker* is not None, it defines a function to convert the received bytes string into an object.

**tunnel\_send**(*obj*, *packer*=None)

Send data through the socket tunnel.

If *packer* is not None, it defines a function to convert *obj* to a bytes string.

`pylablib.core.utils.rpyc_utils.run_device_service(port=18812, verbose=False)`

Start *DeviceService* at the given port

`pylablib.core.utils.rpyc_utils.connect_device_service(addr, port=18812, timeout=3, attempts=2, error_on_fail=True, config=None)`

Connect to the *DeviceService* running at the given address and port

*timeout* and *attempts* define respectively timeout of a single connection attempt, and the number of attempts (RPyC default is 3 seconds timeout and 6 attempts). If *error\_on\_fail==True*, raise error if the connection failed; otherwise, return *None*

## pylablib.core.utils.strdump module

Utils for converting variables into standard python objects (lists, dictionaries, strings, etc.) and back (e.g., for a more predictable LAN transfer). Provides an extension for pickle for more customized classes (numpy arrays, Dictionary).

**class** `pylablib.core.utils.strdump.StrDumper`

Bases: `object`

Class for dumping and loading an object.

Stores procedures for dumping and loading, i.e., conversion from complex classes (such as *Dictionary*) to simple built-in classes (such as *dict* or *str*).

**add\_class**(*cls*, *dumpf=None*, *loadf=None*, *name=None*, *allow\_subclass=True*, *recursive=False*)

Add a rule for dumping/loading an object of class *cls*.

### Parameters

- **cls**
- **dumpf** (*callable*) – Function for dumping an object of the class; *None* means identity function.
- **loadf** (*callable*) – Function for loading an object of the class; *None* means identity function.
- **name** (*str*) – Name of class, which is stored in the packed data (*cls.\_\_name\_\_* by default).
- **allow\_subclass** (*bool*) – If *True*, this rule is also used for subclasses of this class.
- **recursive** (*bool*) – If *True*, the functions are given a second argument, which is a dumping/loading function for their sub-elements.

**dump**(*obj*)

Convert an object into a dumped value

**load**(*obj*)

Convert a dumped value into an object

**loads**(*s*)

Convert a pickled string of a damped object into an object

**dumps**(*obj*)

Dump an object into a pickled string

`pylablib.core.utils.strdump.dumper = <pylablib.core.utils.strdump.StrDumper object>`

Default dumper for converting into standard Python classes and pickling.

Converts `numpy.ndarray` and `Dictionary` objects (these conversion routines are defined when corresponding modules are imported). The converted values include non-printable characters (conversion uses `numpy.load()` and `numpy.ndarray.dump()`), so they can't be saved into text files. However, they're suited for pickling.

`pylablib.core.utils.strdump.dump(obj)`

Convert obj into standard Python classes using the default dumper

`pylablib.core.utils.strdump.load(s)`

Convert standard Python class representation *s* into an object using the default dumper

`pylablib.core.utils.strdump.dumps(obj)`

Convert obj into a pickled string using the default dumper

`pylablib.core.utils.strdump.loads(s)`

Convert a pickled string into an object using the default dumper

## pylablib.core.utils.string module

String search, manipulation and conversion routines.

`pylablib.core.utils.string.string_equal(name1, name2, case_sensitive=True, as_prefix=False)`

Determine if *name1* and *name2* are equal with taking special rules (*case\_sensitive* and *as\_prefix*) into account.

If *as\_prefix*==True, strings match even if *name1* is just a prefix of *name2* (not the other way around).

`pylablib.core.utils.string.find_list_string(name, str_list, case_sensitive=True, as_prefix=False, first_matched=False)`

Find *name* in the string list.

Comparison parameters are defined in `string_equal()`. If *first\_matched*==True, stop at the first match; otherwise if multiple occurrences happen, raise `ValueError`.

### Returns

tuple (index, value).

`pylablib.core.utils.string.find_dict_string(name, str_dict, case_sensitive=True, as_prefix=False)`

Find name in the string dictionary.

Comparison parameters are defined in `string_equal()`. If multiple occurrences happen, raise `ValueError`.

### Returns

tuple (key, value).

`pylablib.core.utils.string.find_first_entry(line, elements, start=0, not_found_value=-1)`

Find the index of the earliest position inside the *line* of any of the strings in *elements*, starting from *start*.

If none are found, return *not\_found\_value*.

`pylablib.core.utils.string.find_all_first_locations(line, elements, start=0, not_found_value=-1, known_locations=None)`

Find the indices of the earliest position inside the *line* of all of the strings in *elements*, starting from *start*.

Return dict {*element*: *pos*}, where *pos* is either position in the string, or *not\_found\_value* if no entries are present. *known\_locations* can specify a dictionary of already known locations of some of the elements. In this case, only missing elements or elements located before *start* will be re-evaluated.

`pylablib.core.utils.string.translate_string_filter(filt, syntax, match_case=True, default=False)`

Turns *filt* into a matching function.

The matching function takes single `str` argument, returns `bool` value.

*filt* can be

- `None`: function always returns default,
- `bool`: function always returns this value,
- `str`: pattern, determined by *syntax*,
- anything else: returned as is (assumed to already be a callable).

*syntax* can be `'re'` (`re`), `'glob'` (`glob`) or `'pred'` (simply matching predicate). *match\_case* determines whether the filter cares about the string case when matching.

**class** `pylablib.core.utils.string.StringFilter(include=None, exclude=None, syntax='re', match_case=False)`

Bases: `object`

String filter function.

Matches string if it matches include (matches all strings by default) and doesn't match exclude (matches nothing by default).

#### Parameters

- **include** – Inclusion filter (translated by `translate_string_filter()` with syntax specified by *syntax*); include all by default.
- **exclude** – Exclusion filter (translated by `translate_string_filter()` with syntax specified by *syntax*); exclude none by default.
- **syntax** – Default syntax for pattern filters. Can be `'re'` (`re`), `'glob'` (`glob`) or `'pred'` (simply matching predicate).
- **match\_case** (`bool`) – Determines whether filter ignores case when matching.

`pylablib.core.utils.string.get_string_filter(include=None, exclude=None, syntax='re', match_case=False)`

Generate `StringFilter` with the given parameters.

If the first argument is already `StringFilter`, return as is. If it's a tuple, expand as argument list.

`pylablib.core.utils.string.sfglob(include=None, exclude=None)`

Return string filter based on `glob` syntax

`pylablib.core.utils.string.sfregex(include=None, exclude=None, match_case=False)`

Return string filter based on `re` syntax

`pylablib.core.utils.string.filter_string_list(l, filt)`

Filter string list based on the filter

`pylablib.core.utils.string.escape_string(value, location='element', escape_convertible=True, quote_type='')`

Escape string.

Escaping can be partially skipped depending on *location*:

- **"parameter"**: escape only if it contains hard delimiters (`"\n\t\v\r"`) anywhere or `_border_escaped` (`"`, `'` or space) on the sides (suited for parameters taking the full string);

- "entry": same as above, plus containing soft delimiters ( , or space) anywhere (suited for entries of a table);
- "element": always escaped

If `escape_convertible==True`, escape strings which can be misinterpreted as other values, such as "1" or "[]";

otherwise, escape only strings which contain special characters.

If `quote_type` is not `None`, automatically put the string into the specified quotation marks;

if `quote_type` is `None`, all quotation marks are escaped; if it's not `None`, only `quote_type` marks are escaped.

**class** `pylablib.core.utils.string.TConversionClass(label, cls, rep, conv)`

Bases: `tuple`

**cls**

**conv**

**label**

**rep**

`pylablib.core.utils.string.add_conversion_class(label, cls, rep, conv)`

Add a string conversion class.

Some values (e.g., numpy arrays or named tuples) lose some of their associated information when converted into strings. With this function is possible to define custom conversion rules for such classes.

#### Parameters

- **label** (*str*) – class label (e.g., "array")
- **cls** – class which is used to determine if the value should use this conversion functions (e.g., `np.ndarray`)
- **rep** – function which takes a single argument (object of class *cls*) and returns its representations; can return a string or an object which is easier to convert to a string (e.g., a list or a tuple)
- **conv** – function which takes one or several arguments (converted values of the class representation) and returns the corresponding object; if *rep* returns a tuple, treat it as a list of several arguments, which are passed to *conv* separately; otherwise, *conv* gets a single argument which is the result of *rep*

When converting to string, if an object of class *cls* is encountered, it is converted in a string `label(str_rep)` (e.g., `"array([0, 1, 2])"`), where *str\_rep* is the result of calling *rep* (if this result is a tuple, avoid double parentheses, e.g., if the result is a tuple `(1, 2)`, the string becomes `"label(1, 2)"` instead of `"label((1, 2))"`). When converting from string, the values inside the parentheses are passed as arguments to *conv* function to get the resulting value.

`pylablib.core.utils.string.add_namedtuple_class(cls)`

Add conversion class for a given named tuple class.

For details, see `add_conversion_class()`.

`pylablib.core.utils.string.to_string(value, location='element', value_formats=None, parenthesis_rules='text', use_classes=False)`

Convert value to string with an option of modifying format string.

#### Parameters

- **value**

- **location** (*str*) – Used for converting strings (see [escape\\_string\(\)](#)).
- **value\_formats** (*dict*) – dictionary {*value\_type*: *fmt*}, where *value\_type* can be *int*, *float* or *complex* and *fmt* is a format string used to represent value of this type (e.g., "5.3f"); default formats are {*float*:".12E", *complex*:".12E", *int*:"d"}.
- **parenthesis\_rules** (*str*) – determine how to deal with single-element tuples and complex numbers can be "text" (single-element tuples are represented with simple parentheses, e.g., "(1)"; complex number are represented without parentheses, e.g., "1+2j") or "python" (single-element tuples are represented with a comma in the end, e.g., "(1,); complex number are represented with parentheses, e.g., "(1+2j)").
- **use\_classes** (*bool*) – if *True*, use additional representation classes for special objects (e.g., numpy arrays will be represented as "array([1, 2, 3])" instead of just "[1, 2, 3]"). This improves conversion fidelity, but makes result harder to parse (e.g., by external string parsers). See [add\\_conversion\\_class\(\)](#) for more explanation.

`pylablib.core.utils.string.is_convertible(value)`

Check if the value can be converted to a string using standard [to\\_string\(\)](#) function.

`pylablib.core.utils.string.extract_escaped_string(line, start=0)`

Extract escaped string in quotation marks from the *line*, starting from *start*.

*line[start]* should be a quotation mark (' or ") or *r* or *b* followed by a quotation mark (for raw or binary strings).

#### Returns

tuple (end position, un-escaped string).

`pylablib.core.utils.string.unescape_string(value)`

Un-escape string.

Only attempt if the string starts a quotation mark " or '. Otherwise (including strings like 'r"' or 'b"'), return the string as is. Raise an error if the string starts with a quotation mark, but does not correspond to a proper escaped string (e.g., '"abc or '"abc"def).

`pylablib.core.utils.string.to_range(range_tuple)`

`pylablib.core.utils.string.from_string(value, case_sensitive=True, parenthesis_rules='text', use_classes=True)`

Parse a string.

Recognizes integers, floats, complex numbers (with *i* or *j* for complex part), strings (in quotation marks), dicts, sets, list and tuples, booleans and *None*. If item is unrecognizable, assumed to be a string.

#### Parameters

- **case\_sensitive** (*bool*) – applied when compared to *None*, *True* or *False*.
- **parenthesis\_rules** (*str*) – determines how to deal with empty entries (e.g., [1, , 3]) and complex number representation ("1+2j" vs. "(1+2j)"):
  - 'text': any empty entries are translated into `empty_string` (i.e., [ , ] -> [`empty_string`, `empty_string`]), except for completely empty structures ([ ] or ( )); complex numbers are represented without parentheses, so that "(1+2j)" will be interpreted as a single-element tuple (1+2j, ).
  - 'python': empty entries in the middle are not allowed; empty entries at the end are ignored (i.e., [2, ] -> [2]) (single-element tuple can still be expressed in two ways: (e, ) or (e)); complex numbers are by default represented with parentheses, so that



"(1+2j)" will be interpreted as a complex number, and only (1+2j,), ((1+2j)) or ((1+2j),) as a single-element tuple.

- **use\_classes** (*bool*) – if *True*, use additional representation classes for special objects (e.g., "array([1, 2, 3])" will be converted into a numpy array instead of raising an error). See [add\\_conversion\\_class\(\)](#) for more explanation.

```
pylablib.core.utils.string.from_string_partial(value, delimiters=re.compile('\s*|\s*|\s+'),
                                              case_sensitive=True, parenthesis_rules='text',
                                              use_classes=True, return_string=False)
```

Convert the first part of the supplied string (bounded by *delimiters*) into a value.

*delimiters* is a string or a regexp (default is "\s\*,\s\*|\s+", i.e., comma or spaces). If *return\_string==False*, convert the value string and return tuple (end\_position, converted\_value); otherwise, return tuple (end\_position, value\_string).

The rest of the parameters is the same as in [from\\_string\(\)](#).

```
pylablib.core.utils.string.from_row_string(value, delimiters=re.compile('\s*|\s*|\s+'),
                                          case_sensitive=True, parenthesis_rules='text',
                                          use_classes=True, return_string=False)
```

Convert the row string into a list of values, separated by delimiters.

If *return\_string==False*, return list of converted objects; otherwise, return list of unconverted strings.

The rest of the parameters is the same as in [from\\_string\\_partial\(\)](#).

## pylablib.core.utils.strpack module

Utilities for packing values into bitstrings. Small extension of the struct module.

```
pylablib.core.utils.strpack.int2bytes(val, l, bo='>')
```

Convert integer into a list of bytes of length *l*.

*bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

```
pylablib.core.utils.strpack.bytes2int(val, bo='>')
```

Convert a list of bytes into an integer.

*bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

```
pylablib.core.utils.strpack.int2bits(val, l, bo='>')
```

Convert integer into a list of bits of length *l*.

*bo* determines byte (and bit) order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

```
pylablib.core.utils.strpack.bits2int(val, bo='>')
```

Convert a list of bits into an integer.

*bo* determines byte (and bit) order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

```
pylablib.core.utils.strpack.pack_uint(val, l, bo='>')
```

Convert an unsigned integer into a bytestring of length *l*.

Return bytes object. *bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

```
pylablib.core.utils.strpack.pack_int(val, l, bo='>')
```

Convert a signed integer into a bytestring of length *l*.

Return bytes object. *bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

`pylablib.core.utils.strpack.unpack_uint(msg, bo='>')`

Convert a bytestring into an unsigned integer.

*bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

`pylablib.core.utils.strpack.unpack_int(msg, bo='>')`

Convert a bytestring into an signed integer.

*bo* determines byte order: '>' is big-endian (MSB first), '<' is little-endian (LSB first).

`pylablib.core.utils.strpack.unpack_numpy_u12bit(buffer, byteorder='<', count=-1)`

## pylablib.core.utils.units module

Routines for conversion of physical units.

`pylablib.core.utils.units.split_units(value)`

Split string value with a dimension.

Return tuple (*val*, *unit*), where *val* is the float part of the value, and *unit* is the string representing units.

`pylablib.core.utils.units.convert_length_units(value, value_unit='m', result_unit='m',  
case_sensitive=True)`

Convert *value* from *value\_unit* to *result\_unit*.

The possible length units are 'm', 'mm', 'um', 'nm', 'pm', 'fm'. If *case\_sensitive*==True, matching units is case sensitive.

`pylablib.core.utils.units.convert_time_units(value, value_unit='s', result_unit='s',  
case_sensitive=True)`

Convert *value* from *value\_unit* to *result\_unit*.

The possible time units are 's', 'ms', 'us', 'ns', 'ps', 'fs', 'as'. If *case\_sensitive*==True, matching units is case sensitive.

`pylablib.core.utils.units.convert_frequency_units(value, value_unit='Hz', result_unit='Hz',  
case_sensitive=True)`

Convert *value* from *value\_unit* to *result\_unit*.

The possible frequency units are 'Hz', 'kHz', 'MHz', 'GHz'. If *case\_sensitive*==True, matching units is case sensitive.

`pylablib.core.utils.units.convert_power_units(value, value_unit='dBm', result_unit='dBm',  
case_sensitive=True, impedance=50.0)`

Convert *value* from *value\_unit* to *result\_unit*.

For conversion between voltage and power, assume RMS voltage and the given *impedance*. The possible power units are 'dBm', 'dBmV', 'dBuV', 'W', 'mW', 'uW', 'nW', 'mV', 'nV'. If *case\_sensitive*==True, matching units is case sensitive.

## Module contents

## Module contents

### pylablib.devices package

## Subpackages

### pylablib.devices.AWG package

## Submodules

### pylablib.devices.AWG.generic module

**exception** pylablib.devices.AWG.generic.**GenericAWGError**

Bases: *DeviceError*

Generic AWG error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.AWG.generic.**GenericAWGBackendError**(*exc*)

Bases: *GenericAWGError*, *DeviceBackendError*

AWG backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.AWG.generic.**GenericAWG**(*addr*)

Bases: *SCPIDevice*

Generic arbitrary wave generator, based on Agilent 33500.

With slight modifications works for many other AWGs using largely the same syntax.

**Error**

alias of *GenericAWGError*

**ReraiseError**

alias of *GenericAWGBackendError*

**get\_channels\_number()**

Get the number of channels

**get\_current\_channel()**

Get current channel

**select\_current\_channel(channel)**

Select current default channel

**is\_output\_enabled(channel=None)**

Check if the output is enabled

**enable\_output(enabled=True, channel=None)**

Turn the output on or off

**get\_output\_polarity(channel=None)**

Get output polarity.

Can be either "norm" or "inv".

**set\_output\_polarity(polarity='norm', channel=None)**

Set output polarity.

Can be either "norm" or "inv".

**is\_sync\_output\_enabled(channel=None)**

Check if SYNC output is enabled

**enable\_sync\_output(enabled=True, channel=None)**

Enable or disable SYNC output

**get\_load(channel=None)**

Get the output load

**set\_load(load=None, channel=None)**

Set the output load (None means High-Z)

**get\_function(channel=None)**

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_function(func, channel=None)**

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_amplitude(channel=None)**

Get output amplitude (i.e., half of the span)

**set\_amplitude(amplitude, channel=None)**

Set output amplitude (i.e., half of the span)

**get\_offset(channel=None)**

Get output offset

**set\_offset(offset, channel=None)**

Set output offset

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (*vmin*, *vmax*) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**set\_output\_range**(*rng*, *channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**get\_frequency**(*channel=None*)

Get output frequency

**set\_frequency**(*frequency*, *channel=None*)

Set output frequency

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**sync\_phase**()

Synchronize phase between two channels

**get\_duty\_cycle**(*channel=None*)

Get output duty cycle (in percent).

Only applies to "square" output function.

**set\_duty\_cycle**(*dcycle*, *channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**enable\_burst**(*enabled=True*, *channel=None*)

Enable burst mode

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to None

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**set\_gate\_polarity**(*polarity='norm', channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**set\_trigger\_source**(*src, channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_slope**(*slope, channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**enable\_trigger\_output**(*enabled=True, channel=None*)

Enable trigger output

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**BackendError**

alias of *DeviceBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_output\_trigger\_slope**(*slope, channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)



**using\_write\_buffer()**

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**pylablib.devices.AWG.specific module**

**class** pylablib.devices.AWG.specific.**Agilent33500**(*addr*, *channels\_number*='auto')

Bases: *GenericAWG*

Agilent 33500 AWG.

**Parameters**

**channels\_number** – number of channels; if "auto", try to determine automatically (by certain commands causing errors)

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *GenericAWGError*

**ReraiseError**

alias of *GenericAWGBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**enable\_burst**(*enabled*=True, *channel*=None)

Enable burst mode

**enable\_output**(*enabled*=True, *channel*=None)

Turn the output on or off

**enable\_sync\_output**(*enabled*=True, *channel*=None)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled*=True, *channel*=None)

Enable trigger output

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**get\_amplitude**(*channel*=None)

Get output amplitude (i.e., half of the span)

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number**()

Get the number of channels

**get\_current\_channel**()

Get current channel

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle**(*channel=None*)

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_frequency**(*channel=None*)

Get output frequency

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function**(*channel=None*)

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load**(*channel=None*)

Get the output load

**get\_offset**(*channel=None*)

Get output offset

**get\_output\_polarity**(*channel=None*)

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to *None*

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle, channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency, channel=None*)

Set output frequency

**set\_function**(*func, channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm', channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None, channel=None*)

Set the output load (*None* means High-Z)

**set\_offset**(*offset, channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm', channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng, channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope, channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase, channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width, channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm, channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None*, *wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg=None*, *arg\_type=None*, *unit=None*, *bool\_selector=None*, *wait\_sync=None*, *read\_echo=False*, *read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.

- **bool\_selector** (*tuple*) – A tuple (false\_value, true\_value) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.AWG.specific.Agilent33220A(addr)`

Bases: `GenericAWG`

Agilent 33220A AWG.

**BackendError**

alias of `DeviceBackendError`

**Error**

alias of `GenericAWGError`

**ReraiseError**

alias of `GenericAWGBackendError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_burst**(*enabled*=True, *channel*=None)

Enable burst mode

**enable\_output**(*enabled*=True, *channel*=None)

Turn the output on or off

**enable\_sync\_output**(*enabled*=True, *channel*=None)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled*=True, *channel*=None)

Enable trigger output

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If `one_line==True`, read only a single line.



**get\_amplitude**(*channel=None*)

Get output amplitude (i.e., half of the span)

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number**()

Get the number of channels

**get\_current\_channel**()

Get current channel

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle**(*channel=None*)

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_frequency**(*channel=None*)

Get output frequency

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function**(*channel=None*)

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load**(*channel=None*)

Get the output load

**get\_offset**(*channel=None*)

Get output offset

**get\_output\_polarity**(*channel=None*)

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode*, *channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1*, *channel=None*)

Set burst mode ncycles.

Infinite corresponds to None

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle*, *channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency*, *channel=None*)

Set output frequency

**set\_function**(*func*, *channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm'*, *channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None*, *channel=None*)

Set the output load (None means High-Z)

**set\_offset**(*offset*, *channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm'*, *channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng*, *channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope*, *channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform [wait\\_sync\(\)](#)), 'dev' (perform [wait\\_dev\(\)](#)) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None*, *wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg=None*, *arg\_type=None*, *unit=None*, *bool\_selector=None*, *wait\_sync=None*,  
*read\_echo=False*, *read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{: .3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'`

with `arg=[1,2]` will produce a string `'1;2'`); if a list of types is used, each element of `arg` is converted using the corresponding type, and the result is joined with `","`.

- **unit** (*str*) – If not `None`, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (`false_value`, `true_value`) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if `True`, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (`False` by default).
- **read\_echo** (*bool*) – If `True`, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.AWG.specific.InstekAFG2225(addr)`

Bases: `GenericAWG`

Instek AFG2225 AWG.

Compared to 2000/2100 series, has one extra channel and a bit more capabilities (burst trigger, pulse function)

**get\_offset**(*channel=None*)

Get output offset

**set\_offset**(*offset, channel=None*)

Set output offset

**get\_amplitude**(*channel=None*)

Get output amplitude (i.e., half of the span)

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**BackendError**

alias of `DeviceBackendError`

**Error**

alias of `GenericAWGError`

**ReraiseError**

alias of `GenericAWGBackendError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict `{name: value}` of the available device settings. Non-applicable settings are ignored.

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_burst**(*enabled=True, channel=None*)

Enable burst mode

**enable\_output**(*enabled=True, channel=None*)

Turn the output on or off

**enable\_sync\_output**(*enabled=True, channel=None*)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled=True, channel=None*)

Enable trigger output

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number**()

Get the number of channels

**get\_current\_channel**()

Get current channel

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle**(*channel=None*)

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_frequency**(*channel=None*)

Get output frequency

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function**(*channel=None*)

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load**(*channel=None*)

Get the output load

**get\_output\_polarity**(*channel=None*)

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.



**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to *None*

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle, channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency, channel=None*)

Set output frequency

**set\_function**(*func, channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm', channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None, channel=None*)

Set the output load (*None* means High-Z)

**set\_output\_polarity**(*polarity='norm', channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng, channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope, channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None*, *wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg=None*, *arg\_type=None*, *unit=None*, *bool\_selector=None*, *wait\_sync=None*, *read\_echo=False*, *read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.

- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.AWG.specific.InstekAFG2000(addr)`

Bases: `InstekAFG2225`

Instek AFG2000/2100 series AWG.

Compared to AFG2225, has only one channel and fewer capabilities.

**BackendError**

alias of `DeviceBackendError`

**Error**

alias of `GenericAWGError`

**ReraiseError**

alias of `GenericAWGBackendError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_burst**(*enabled*=True, *channel*=None)

Enable burst mode

**enable\_output**(*enabled*=True, *channel*=None)

Turn the output on or off

**enable\_sync\_output**(*enabled=True, channel=None*)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled=True, channel=None*)

Enable trigger output

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**get\_amplitude**(*channel=None*)

Get output amplitude (i.e., half of the span)

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number**()

Get the number of channels

**get\_current\_channel**()

Get current channel

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle**(*channel=None*)

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_frequency**(*channel=None*)

Get output frequency

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function**(*channel=None*)

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load**(*channel=None*)

Get the output load

**get\_offset**(*channel=None*)

Get output offset

**get\_output\_polarity**(*channel=None*)

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to *None*

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle, channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency, channel=None*)

Set output frequency

**set\_function**(*func, channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm', channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None, channel=None*)

Set the output load (*None* means High-Z)

**set\_offset**(*offset, channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm', channel=None*)

Set output polarity.

Can be either "norm" or "inv".



**set\_output\_range**(*rng*, *channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope*, *channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., *arg\_type*='{0};{1}' with *arg*=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if *read\_echo*==True.

**class** `pylablib.devices.AWG.specific.RSInstekAFG21000(addr)`

Bases: `InstekAFG2000`

RS Instek AFG21000 series AWG.

Compared to Instek AFG2000, it takes care of the amplitude output bug.

**get\_offset**(*channel=None*)

Get output offset

**get\_amplitude**(*channel=None*)

Get output amplitude (i.e., half of the span)

**BackendError**

alias of `DeviceBackendError`

**Error**

alias of `GenericAWGError`

**ReraiseError**

alias of `GenericAWGBackendError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**enable\_burst**(*enabled*=True, *channel*=None)

Enable burst mode

**enable\_output**(*enabled*=True, *channel*=None)

Turn the output on or off

**enable\_sync\_output**(*enabled*=True, *channel*=None)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled*=True, *channel*=None)

Enable trigger output

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel*=None)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel*=None)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number**()

Get the number of channels

**get\_current\_channel**()

Get current channel

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle**(*channel*=None)

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr**(*timeout*=None)

Get the device status register (by default, "\*ESR?" command)

**get\_frequency**(*channel=None*)

Get output frequency

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function**(*channel=None*)

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity**(*channel=None*)

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load**(*channel=None*)

Get the output load

**get\_output\_polarity**(*channel=None*)

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (*vmin*, *vmax*) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this

callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to *None*

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle, channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency, channel=None*)

Set output frequency

**set\_function**(*func, channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm', channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None, channel=None*)

Set the output load (*None* means High-Z)

**set\_offset**(*offset, channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm', channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng, channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope, channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase, channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width, channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm, channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope, channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src, channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.AWG.specific.TektronixAFG1000`(*addr, channels\_number='auto'*)

Bases: `GenericAWG`

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.



**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *GenericAWGError*

**ReraiseError**

alias of *GenericAWGBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type='string'*, *delay=0.0*, *timeout=None*, *read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_burst**(*enabled=True*, *channel=None*)

Enable burst mode

**enable\_output**(*enabled=True*, *channel=None*)

Turn the output on or off

**enable\_sync\_output**(*enabled=True*, *channel=None*)

Enable or disable SYNC output

**enable\_trigger\_output**(*enabled=True*, *channel=None*)

Enable trigger output

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**get\_amplitude**(*channel=None*)

Get output amplitude (i.e., half of the span)

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_burst\_mode**(*channel=None*)

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles**(*channel=None*)

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number()**

Get the number of channels

**get\_current\_channel()**

Get current channel

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle(channel=None)**

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_frequency(channel=None)**

Get output frequency

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function(channel=None)**

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity(channel=None)**

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load(channel=None)**

Get the output load

**get\_offset(channel=None)**

Get output offset

**get\_output\_polarity(channel=None)**

Get output polarity.

Can be either "norm" or "inv".

**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: b'#', then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude, channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode, channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1, channel=None*)

Set burst mode ncycles.

Infinite corresponds to None

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle, channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency*, *channel=None*)

Set output frequency

**set\_function**(*func*, *channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm'*, *channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None*, *channel=None*)

Set the output load (None means High-Z)

**set\_offset**(*offset*, *channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm'*, *channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng*, *channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope*, *channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**sync\_phase**()

Synchronize phase between two channels

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer()**

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with `;` delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with `" , "`.
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as `'{: .3f}'`) or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string `'1;2'`); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with `" , "`.
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** pylablib.devices.AWG.specific.RigolDG1000(*addr*)

Bases: `GenericAWG`

Rigol DG1000 AWG.

**sync\_phase()**

Synchronize phase between two channels

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *GenericAWGError*

**ReraiseError**

alias of *GenericAWGBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_burst(enabled=True, channel=None)**

Enable burst mode

**enable\_output(enabled=True, channel=None)**

Turn the output on or off

**enable\_sync\_output(enabled=True, channel=None)**

Enable or disable SYNC output

**enable\_trigger\_output(enabled=True, channel=None)**

Enable trigger output

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**get\_amplitude(channel=None)**

Get output amplitude (i.e., half of the span)

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_burst\_mode(channel=None)**

Get burst mode.

Can be either "trig" or "gate".

**get\_burst\_ncycles(channel=None)**

Get burst mode ncycles.

Infinite corresponds to a large value (>1E37).

**get\_channels\_number()**

Get the number of channels

**get\_current\_channel()**

Get current channel

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_duty\_cycle(channel=None)**

Get output duty cycle (in percent).

Only applies to "square" output function.

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_frequency(channel=None)**

Get output frequency

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_function(channel=None)**

Get output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**get\_gate\_polarity(channel=None)**

Get burst gate polarity.

Can be either "norm" or "inv".

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_load(channel=None)**

Get the output load

**get\_offset(channel=None)**

Get output offset

**get\_output\_polarity(channel=None)**

Get output polarity.

Can be either "norm" or "inv".



**get\_output\_range**(*channel=None*)

Get output voltage range.

Return tuple (vmin, vmax) with the low and high voltage values (i.e., offset-amplitude and offset+amplitude).

**get\_output\_trigger\_slope**(*channel=None*)

Get output trigger slope.

Can be either "pos", or "neg".

**get\_phase**(*channel=None*)

Get output phase (in degrees)

**get\_pulse\_width**(*channel=None*)

Get output pulse width (in seconds).

Only applies to "pulse" output function.

**get\_ramp\_symmetry**(*channel=None*)

Get output ramp symmetry (in percent).

Only applies to "ramp" output function.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_slope**(*channel=None*)

Get trigger slope.

Can be either "pos", or "neg".

**get\_trigger\_source**(*channel=None*)

Get trigger source.

Can be either "imm", "ext", or "bus".

**is\_burst\_enabled**(*channel=None*)

Check if the burst mode is enabled

**is\_opened**()

Check if the device is connected

**is\_output\_enabled**(*channel=None*)

Check if the output is enabled

**is\_sync\_output\_enabled**(*channel=None*)

Check if SYNC output is enabled

**is\_trigger\_output\_enabled**(*channel=None*)

Check if the trigger output is enabled

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**static parse\_array\_data**(*data*, *fmt*, *include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string'*, *timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False*, *timeout=None*, *flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True*, *ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset()**

Reset the device (by default, "\*RST" command)

**select\_current\_channel**(*channel*)

Select current default channel

**set\_amplitude**(*amplitude*, *channel=None*)

Set output amplitude (i.e., half of the span)

**set\_burst\_mode**(*mode*, *channel=None*)

Set burst mode.

Can be either "trig" or "gate".

**set\_burst\_ncycles**(*ncycles=1*, *channel=None*)

Set burst mode ncycles.

Infinite corresponds to None

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_duty\_cycle**(*dcycle*, *channel=None*)

Set output duty cycle (in percent).

Only applies to "square" output function.

**set\_frequency**(*frequency*, *channel=None*)

Set output frequency

**set\_function**(*func*, *channel=None*)

Set output function.

Can be one of the following: "sine", "square", "ramp", "pulse", "noise", "prbs", "DC", "user", "arb". Not all functions can be available, depending on the particular model of the generator.

**set\_gate\_polarity**(*polarity='norm'*, *channel=None*)

Set burst gate polarity.

Can be either "norm" or "inv".

**set\_load**(*load=None*, *channel=None*)

Set the output load (None means High-Z)

**set\_offset**(*offset*, *channel=None*)

Set output offset

**set\_output\_polarity**(*polarity='norm'*, *channel=None*)

Set output polarity.

Can be either "norm" or "inv".

**set\_output\_range**(*rng*, *channel=None*)

Set output voltage range.

If span is less than 1E-4, automatically switch to DC mode.

**set\_output\_trigger\_slope**(*slope*, *channel=None*)

Set output trigger slope.

Can be either "pos", or "neg".

**set\_phase**(*phase*, *channel=None*)

Set output phase (in degrees)

**set\_pulse\_width**(*width*, *channel=None*)

Set output pulse width (in seconds).

Only applies to "pulse" output function.

**set\_ramp\_symmetry**(*rsymm*, *channel=None*)

Set output ramp symmetry (in percent).

Only applies to "ramp" output function.

**set\_trigger\_slope**(*slope*, *channel=None*)

Set trigger slope.

Can be either "pos", or "neg".

**set\_trigger\_source**(*src*, *channel=None*)

Set trigger source.

Can be either "imm", "ext", or "bus".

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive **write**() operations are bundled together with ; delimiter. The actual write is performed at the **read**()/**ask**() operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform **wait\_sync**()), 'dev' (perform **wait\_dev**()) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{: .3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., **arg\_type**='{0};{1}' with **arg**=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use **.\_bool\_selector** attribute.
- **wait\_sync** – if True, append the sync command (specified as **.\_wait\_sync\_comm** attribute, **"\*OPC?"** by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default **.\_default\_write\_sync** attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if **read\_echo**==True.

## Module contents

### pylablib.devices.Agilent package

#### Submodules

#### pylablib.devices.Agilent.base module

**exception** `pylablib.devices.Agilent.base.AgilentError`

Bases: `DeviceError`

Generic Agilent device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Agilent.base.AgilentBackendError`(*exc*)

Bases: `AgilentError`, `DeviceBackendError`

Generic Agilent backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

#### pylablib.devices.Agilent.pressure module

**class** `pylablib.devices.Agilent.pressure.TXGS600DeviceInfo`(*main\_board\_rev*, *boards\_rev*)

Bases: `tuple`

**boards\_rev**

**main\_board\_rev**

**class** `pylablib.devices.Agilent.pressure.XGS600`(*conn*, *addr=0*)

Bases: `ICommBackendWrapper`

Agilent XGS-600 pressure gauge controller.

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **addr** – device address if RS485 communication is used (for RS232 must be kept 0)

#### Error

alias of `AgilentError`

**query**(*comm*, *arg=""*)

Send the command (with an optional arguments) to the device and return the result

**get\_device\_info**()

Get device info as a tuple (main\_board\_rev, boards\_rev)

**list\_boards**()

Return a list of the board types installed.

The type can be "HFIG", "IMG", "CNV", "analog", or "none".

**get\_units**()

Get device units for indication/reading ("mbar", "torr", or "pa")

**set\_units**(*units*)

Set device units for indication/reading ("mbar", "torr", or "pa")

**to\_Pa**(*value*, *units=None*)

Convert value in the given units to Pa.

If *units* is None, use the current display units.

**from\_Pa**(*value*, *units=None*)

Convert value in the given units from Pa.

If *units* is None, use the current display units.

**get\_all\_pressures**(*display\_units=False*)

Get pressures of all available gauges as a list.

Includes pressures from all the connected cards from left to right (front view). If the gauge is not connected, the value is "nochl".

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.AlliedVision package

#### Submodules

#### pylablib.devices.AlliedVision.Bonito module

**exception** pylablib.devices.AlliedVision.Bonito.**BonitoError**

Bases: *DeviceError*

Generic AlliedVision Bonito error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.AlliedVision.Bonito.**TDeviceInfo**(*version, serial\_number, grabber\_info*)

Bases: *tuple*

**grabber\_info**

**serial\_number**

**version**

**class** pylablib.devices.AlliedVision.Bonito.**IBonitoCamera**(\*\*kwargs)

Bases: *ICamera*

**Error**

alias of *DeviceError*

**GrabberClass** = None

**open**()

Open the connection

**serial\_query**(query, timeout=3.0)

**get\_serial\_parameter**(comm, kind='int', timeout=3.0)

**set\_serial\_parameter**(comm, value)

**get\_device\_info**()

Get camera model data.

Return tuple (model, serial\_number, grabber\_info).

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (width, height); as the camera does not provide this information, use the frame grabber parameters

**get\_roi**()

Get current ROI.

Return tuple (hstart, hend, vstart, vend).

**set\_roi**(hstart=0, hend=None, vstart=0, vend=None)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**get\_roi\_limits**(hbin=1, vbin=1)

**setup\_acquisition**(mode='sequence', nframes=100)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**get\_exposure\_control\_mode**()

Get the exposure control mode.

Return tuple (timing\_mode, feature\_mode), where *timing\_mode* determines how the exposure and frame period are timed (continuous, external trigger control, internal control, etc.), and *feature\_mode* controls additional features (permanent exposure, enhanced full well mode). See documentation for details.

**set\_exposure\_control\_mode**(timing\_mode=None, feature\_mode=None)

Set the exposure control mode.

*timing\_mode* determines how the exposure and frame period are timed (continuous, external trigger control, internal control, etc.), and *feature\_mode* controls additional features (permanent exposure, enhanced full well mode). See documentation for details.



**get\_exposure()**

Get current exposure.

Note that the actual exposure might be different, depending on the exposure control mode.

**set\_exposure(*exposure*, *setup\_mode*=True)**

Set current exposure.

Note that the actual exposure might be different, depending on the exposure control mode. If `setup_mode==True`, automatically set the exposure mode to take the given exposure value into account.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode).

Note that the actual frame period might be different, depending on the exposure control mode.

**set\_frame\_period(*frame\_period*, *setup\_mode*=True)**

Set frame period (time between two consecutive frames in the internal trigger mode).

Note that the actual frame period might be different, depending on the exposure control mode. If `setup_mode==True`, automatically set the exposure mode to take the given exposure value into account.

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (`exposure`, `frame_period`).

**is\_status\_line\_enabled()**

Check if the status line is on

**enable\_status\_line(*enabled*=True)**

Enable or disable status line

**get\_black\_level\_offset()**

Get the black level offset

**set\_black\_level\_offset(*offset*)**

Set the black level offset

**get\_digital\_gain()**

Get the digital gain (0 for 1x, 1 for 2x, 2 for 4x)

**set\_digital\_gain(*gain*)**

Get the digital gain (0 for 1x, 1 for 2x, 2 for 4x)

**FrameTransferError**

alias of *DefaultFrameTransferError*

**TimeoutError**

alias of *DeviceError*

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**close()**

Close the connection

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing(*indexing*)**

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap(*timeout=5.0, return\_info=False*)**

Snap a single frame

**start\_acquisition(\**args*, \*\**kwargs*)**

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**wait\_for\_frame(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)**

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class pylablib.devices.AlliedVision.Bonito.BonitoIMACamera(*imaq\_name='img0'*)**

Bases: [IBonitoCamera](#), [IMAQFrameGrabber](#)

IMAQ+PFCam interface to a AlliedVision Bonito camera.

**Parameters**

**imaq\_name** – IMAQ interface name (can be learned by [IMAQ.list\\_cameras\(\)](#); usually, but not always, starts with "img")

**Error**

alias of [DeviceError](#)

**GrabberClass**

alias of [IMAQFrameGrabber](#)

**FrameTransferError**

alias of [DefaultFrameTransferError](#)

**TimeoutError** = <Mock spec='str' id='140527693277200'>

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear all acquisition details and free all buffers

**clear\_all\_triggers**(*reset\_acquisition=True*)

Disable all triggers of the session

If the input triggers configuration has been changed, acquisition needs to be restart; if *reset\_acquisition==True*, perform it automatically.

**close()**

Close connection to the camera

**configure\_trigger\_in**(*trig\_type*, *trig\_line=0*, *trig\_pol='high'*, *trig\_action='none'*, *timeout=None*, *reset\_acquisition=True*)

Configure input trigger.

**Parameters**

- **trig\_type** (*str*) – trigger source type; can be "ext", "rtsi", "iso\_in", or "software"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_action** (*str*) – trigger action; can be "none" (disable trigger), "capture" (start capturing), "stop" (stop capturing), "buffer" (capture a single frame), or "bufflist" (capture the whole buffer list once)
- **timeout** (*float*) – timeout in seconds; *None* means not timeout.
- **reset\_acquisition** (*bool*) – if the input triggers configuration has been changed, acquisition needs to be restart; if *True*, perform it automatically

**configure\_trigger\_out**(*trig\_type*, *trig\_line=0*, *trig\_pol='high'*, *trig\_drive='disable'*)

Configure trigger output.

**Parameters**

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_drive** (*str*) – trigger output signal; can be "disable" (disable drive), "acq\_in\_progress" (asserted when acquisition is started), "acq\_done" (asserted when acquisition is done), "unasserted" (force unasserted level), "asserted" (force asserted level), "hsync" (asserted on start of a single line start), "vsync" (asserted on start of a frame scan), "frame\_start" (asserted when a single frame is captured), or "frame\_done" (asserted when a single frame is done)

**enable\_status\_line**(*enabled=True*)

Enable or disable status line

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_grabber\_attribute\_values()**

Get a dictionary of all readable attributes.

The attributes types are autodetected, and some of the types of uncommon attributes may be misrepresented.

**get\_black\_level\_offset()**

Get the black level offset

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height); as the camera does not provide this information, use the frame grabber parameters

**get\_device\_info()**

Get camera model data.

Return tuple (model, serial\_number, grabber\_info).

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_digital\_gain()**

Get the digital gain (0 for 1x, 1 for 2x, 2 for 4x)

**get\_exposure()**

Get current exposure.

Note that the actual exposure might be different, depending on the exposure control mode.

**get\_exposure\_control\_mode()**

Get the exposure control mode.

Return tuple (timing\_mode, feature\_mode), where timing\_mode determines how the exposure and frame period are timed (continuous, external trigger control, internal control, etc.), and feature\_mode controls additional features (permanent exposure, enhanced full well mode). See documentation for details.

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode).

Note that the actual frame period might be different, depending on the exposure control mode.

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (`exposure`, `frame_period`).

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_grabber\_attribute\_value(attr, default=None, kind='auto')**

Get value of an attribute with a given name or index.

If *default* is not `None`, return *default* if the attribute is not supported; otherwise, raise an error. *kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (`width`, `height`)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (`hstart`, `hend`, `vstart`, `vend`). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.



Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

#### **get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

#### **get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

#### **get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*).

#### **get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

#### **get\_serial\_parameter(*comm*, *kind='int'*, *timeout=3.0*)**

#### **get\_serial\_params()**

Return serial parameters as a tuple (*write\_term*, *datatype*)

#### **get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

#### **grab(*nframes=1*, *frame\_timeout=5.0*, *missing\_frame='skip'*, *return\_info=False*, *buff\_size=None*)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

#### **is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

#### **is\_opened()**

Check if the device is connected

**is\_status\_line\_enabled()**

Check if the status line is on

**open()**

Open connection to the camera

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (`None` means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (`None` means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by `rng` (by default, all un-read images).

If `rng` is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. `missing_frame` determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied `rng` if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_trigger**(*trig\_type, trig\_line=0, trig\_pol='high'*)

Read current value of a trigger (input or output).

#### Parameters

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", "iso\_in", or "iso\_out"
- **trig\_line** (*int*) – trigger line number

- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"

**reset()**

Reset connection to the camera

**send\_software\_trigger()**

Send software trigger signal

**serial\_flush()**

Flush CameraLink serial port

**serial\_query**(*query*, *timeout=3.0*)

**serial\_read**(*n*, *timeout=3.0*, *datatype=None*)

Read specified number of bytes from CameraLink serial port.

#### Parameters

- **n** – number of bytes to read
- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")

**serial\_readline**(*timeout=3.0*, *datatype=None*, *maxn=1024*)

Read bytes from CameraLink serial port until the termination character (defined in camera file) is encountered.

#### Parameters

- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")
- **maxn** – maximal number of bytes to read

**serial\_write**(*msg*, *timeout=3.0*, *term=None*)

Write message into CameraLink serial port.

#### Parameters

- **timeout** – operation timeout (in seconds)
- **term** – additional write terminator character to add to the message; if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, no additional terminator)

**set\_black\_level\_offset**(*offset*)

Set the black level offset

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_digital\_gain**(*gain*)

Get the digital gain (0 for 1x, 1 for 2x, 2 for 4x)

**set\_exposure**(*exposure*, *setup\_mode*=True)

Set current exposure.

Note that the actual exposure might be different, depending on the exposure control mode. If `setup_mode==True`, automatically set the exposure mode to take the given exposure value into account.

**set\_exposure\_control\_mode**(*timing\_mode*=None, *feature\_mode*=None)

Set the exposure control mode.

*timing\_mode* determines how the exposure and frame period are timed (continuous, external trigger control, internal control, etc.), and *feature\_mode* controls additional features (permanent exposure, enhanced full well mode). See documentation for details.

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt*, *include\_fields*=None)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period*=1)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_frame\_period**(*frame\_period*, *setup\_mode*=True)

Set frame period (time between two consecutive frames in the internal trigger mode).

Note that the actual frame period might be different, depending on the exposure control mode. If `setup_mode==True`, automatically set the exposure mode to take the given exposure value into account.

**set\_grabber\_attribute\_value**(*attr*, *value*, *kind*='int32')

Set value of an attribute with a given name or index.

*kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**set\_grabber\_roi**(*hstart*=0, *hend*=None, *vstart*=0, *vend*=None)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**set\_serial\_parameter**(*comm, value*)**setup\_acquisition**(*mode='sequence', nframes=100*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that [\*IMAQCamera.acquisition\\_in\\_progress\(\)\*](#) would still return True in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**setup\_serial\_params**(*write\_term="", datatype='bytes'*)

Setup default serial communication parameters.

**Parameters**

- **write\_term** – default terminator character to be added to the sent messages
- **datatype** – type of the result of read commands; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(*\*args, \*\*kwargs*)

Start acquisition.

Can take the same keyword parameters as *meth: ``setup\_acquisition``*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [\*setup\\_acquisition\(\)\*](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [\*wait\\_for\\_frame\(\)\*](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**pylablib.devices.AlliedVision.Bonito.check\_grabber\_association**(*cam*)

Check if the given IMAQ frame grabber corresponds to Bonito camera.

*cam* should be an opened instance of [\*IMAQCamera\*](#).

**class** pylablib.devices.AlliedVision.Bonito.TStatusLine(*framestamp*)

Bases: [tuple](#)

**framestamp**

pylablib.devices.AlliedVision.Bonito.get\_status\_lines(*frames*)

Get frame info from the binary status line.

*frames* can be 2D array (one frame), 3D array (stack of frames, first index is frame number), or list of 1D or 2D arrays. Assume that the status line is present; if it isn't, the returned frame info will be a random noise. Return a 1D or 2D numpy array, where the first axis (if present) is the frame number, and the last is the status line entry.

**class** pylablib.devices.AlliedVision.Bonito.BonitoStatusLineChecker

Bases: [StatusLineChecker](#)

**get\_framestamp**(*frames*)

Get framestamps from status lines in the given frames

**check\_indices**(*indices*, *step=1*)

Check if indices are consistent with the given step

## Module contents

### pylablib.devices.Andor package

#### Submodules

#### pylablib.devices.Andor.AndorSDK2 module

**class** pylablib.devices.Andor.AndorSDK2.LibraryController(*lib*)

Bases: [LibraryController](#)

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

```
pylablib.devices.Andor.AndorSDK2.restart_lib()
```

```
pylablib.devices.Andor.AndorSDK2.get_SDK_version()
```

Get version of Andor SDK2

```
pylablib.devices.Andor.AndorSDK2.get_cameras_number()
```

Get number of connected Andor cameras

```
class pylablib.devices.Andor.AndorSDK2.TDeviceInfo(controller_model, head_model, serial_number)
```

Bases: [tuple](#)

**controller\_model**

**head\_model**

**serial\_number**

```
class pylablib.devices.Andor.AndorSDK2.TCycleTimings(exposure, accum_cycle_time,
                                                    kinetic_cycle_time)
```

Bases: [tuple](#)

**accum\_cycle\_time**

**exposure**

**kinetic\_cycle\_time**

```
class pylablib.devices.Andor.AndorSDK2.TAcqProgress(frames_done, cycles_done)
```

Bases: [tuple](#)

**cycles\_done**

**frames\_done**

```
class pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera(idx=0, ini_path="", temperature=None,
                                                         fan_mode='off', amp_mode=None)
```

Bases: [IBinROICamera](#), [IExposureCamera](#)

Andor SDK2 camera.

Due to the library features, the camera needs to set up all of the parameters to some default values upon connection. Most of these parameters are chosen as reasonable defaults: full ROI, minimal exposure time, closed shutter, internal trigger, fastest recommended verticals shift speed, no EMCCD gain. However, some should be supplied during the connection: temperature setpoint (where appropriate), fan mode, and amplifier mode; while there is still a possibility to have default values of these parameters, they might not be appropriate in some settings, and frequently need to be changed.

Caution: the manufacturer DLL is designed such that if the camera is not closed on the program termination, the allocated resources are never released. If this happens, these resources are blocked until the complete OS restart.

#### Parameters

- **idx** (*int*) – camera index (use [get\\_cameras\\_number\(\)](#) to get the total number of connected cameras)
- **ini\_path** (*str*) – path to .ini file, if required by the camera
- **temperature** – initial temperature setpoint (in C); can also be `None` (select the bottom 20% of the whole range), or "off" (turn the cooler off and set the maximal of the whole range)

- **fan\_mode** – initial fan mode
- **amp\_mode** – initial amplifier mode (a tuple like the one returned by `get_amp_mode()`); can also be `None`, which selects the slowest, smallest gain mode

**Error**

alias of [\*AndorError\*](#)

**TimeoutError**

alias of [\*AndorTimeoutError\*](#)

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get camera device info.

Return tuple (controller\_mode, head\_model, serial\_number).

**get\_status()**

Get camera status.

Return either "idle" (no acquisition), "acquiring" (acquisition in progress) or "temp\_cycle" (temperature cycle in progress).

**acquisition\_in\_progress()**

Check if acquisition is in progress

**get\_capabilities()**

Get camera capabilities.

For description of the structure, see Andor SDK manual.

**get\_pixel\_size()**

Get camera pixel size (in m)

**is\_cooler\_on()**

Check if the cooler is on

**set\_cooler(on=True)**

Set the cooler on or off

**get\_temperature\_status()**

Get temperature status.

Can return "off" (cooler off), "not\_reached" (cooling in progress), "not\_stabilized" (reached but not stabilized yet), "stabilized" (completely stabilized) or "drifted".

**get\_temperature()**

Get the current camera temperature (in C)

**set\_temperature(temperature, enable\_cooler=True)**

Change the temperature setpoint (in C).

If enable\_cooler==True, turn the cooler on automatically if present.



**get\_temperature\_setpoint()**

Get the temperature setpoint (in C)

**get\_temperature\_range()**

Return the available range of temperatures (in C)

**get\_all\_amp\_modes()**

Get all available preamp modes.

Each preamp mode is characterized by an AD channel index, amplifier index, channel speed (horizontal scan speed) index and preamp gain index. Return list of tuples (channel, channel\_bitdepth, oamp, oamp\_kind, hsspeed, hsspeed\_MHz, preamp, preamp\_gain), where channel, oamp, hsspeed and preamp are indices, while channel\_bitdepth, oamp\_kind, hsspeed\_MHz and preamp\_gain are descriptions.

**get\_max\_vsspeed()**

Get maximal recommended vertical scan speed

**get\_all\_vsspeeds()**

Get all available vertical shift speeds modes.

Return list of the vertical shift periods in microseconds for the corresponding indices (starting from 0).

**set\_amp\_mode(channel=None, oamp=None, hsspeed=None, preamp=None)**

Setup preamp mode.

Can specify AD channel index, amplifier index, channel speed (horizontal scan speed) index and preamp gain index. *None* (default) means leaving the current value.

**get\_amp\_mode(full=True)**

Return the current amplifier mode.

If *full==True*, return a full description (e.g., actual preamp gain or channel name); otherwise, return just the essential indices information (enough to set the mode for this camera, but no explanations).

**set\_vsspeed(vsspeed)**

Set vertical scan speed index

**get\_channel()**

Get current channel index

**get\_channel\_bitdepth(channel=None)**

Get channel bit depth corresponding to the given channel index (current by default)

**get\_oamp()**

Get current output amplifier index

**get\_oamp\_desc(oamp=None)**

Get output amplifier kind corresponding to the given oamp index (current by default)

**get\_hsspeed()**

Get current horizontal speed index

**get\_hsspeed\_frequency(hsspeed=None)**

Get horizontal scan frequency (in Hz) corresponding to the given hsspeed index (current by default)

**get\_preamp()**

Get current preamp index

**get\_preamp\_gain**(*preamp=None*)

Get preamp gain corresponding to the given preamp index (current by default)

**get\_vsspeed**()

Get current vertical speed index

**get\_vsspeed\_period**(*vsspeed=None*)

Get vertical scan period corresponding to the given vsspeed index (current by default)

**get\_EMCCD\_gain**()

Get current EMCCD gain.

Return tuple (gain, advanced).

**set\_EMCCD\_gain**(*gain, advanced=None*)

Set EMCCD gain.

Gain goes up to 300 if *advanced*==False or higher if *advanced*==True (in this mode the sensor can be permanently damaged by strong light).

**init\_amp\_mode**(*mode=None*)

Initialize the camera channel, frequencies and amp settings to some default mode.

If *mode* is supplied, use this mode; otherwise, use the slowest, lowest gain mode (the first one returned by [get\\_all\\_amp\\_modes\(\)](#)). Also set the maximal recommended vertical shift speed and no EMCCD gain.

**get\_min\_shutter\_times**()

Get minimal shutter opening and closing times

**setup\_shutter**(*mode, ttl\_mode=0, open\_time=None, close\_time=None*)

Setup shutter.

*mode* can be "auto", "open" or "closed", *ttl\_mode* can be 0 (low is open) or 1 (high is open), *open\_time* and *close\_time* specify opening and closing times (required to calculate the minimal exposure times). By default, these time are minimal allowed times.

**get\_shutter\_parameters**()

Return shutter parameters as a tuple (mode, ttl\_mode, open\_time, close\_time)

**get\_shutter**()

Get shutter state ("auto", "open", or "closed")

**set\_fan\_mode**(*mode*)

Set fan mode.

Can be "full", "low" or "off".

**get\_fan\_mode**()

Return fan mode ("full", "low", or "off")

**read\_in\_aux\_port**(*port*)

Get state at a given auxiliary port

**set\_out\_aux\_port**(*port, state*)

Set state at a given auxiliary port

**set\_trigger\_mode(mode)**

Set trigger mode.

Can be "int" (internal), "ext" (external), "ext\_start" (external start), "ext\_exp" (external exposure), "ext\_fvb\_em" (external FVB EM), "software" (software trigger) or "ext\_charge\_shift" (external charge shifting).

For description, see Andor SDK manual.

**get\_trigger\_mode()**

Return trigger mode

**get\_trigger\_level\_limits()**

Get limits on the trigger level

**setup\_ext\_trigger(level=None, invert=None, term\_highZ=None)**

Setup external trigger (level, inversion, and high-Z termination).

Any None values are not changed. If any returned values are None, it means that this option is not supported.

**get\_ext\_trigger\_parameters()**

Return external trigger parameters (level, inversion, high-Z termination).

If any returned values are None, it means that this option is not supported.

**send\_software\_trigger()**

Send software trigger signal

**set\_acquisition\_mode(mode, setup\_params=True)**

Set the acquisition mode.

Can be "single", "accum", "kinetic", "fast\_kinetic" or "cont" (continuous). If `setup_params==True`, make sure that the last specified parameters for this mode are set up. For description of each mode, see Andor SDK manual and corresponding `setup_*_mode` functions.

**get\_acquisition\_mode()**

Get the current acquisition mode

**setup\_accum\_mode(num\_acc, cycle\_time\_acc=0)**

Switch into the accum acquisition mode and set up its parameters.

`num_acc` is the number of accumulated frames, `cycle_time_acc` is the acquisition period (by default the minimal possible based on exposure and transfer time).

**get\_accum\_mode\_parameters()**

Return accum acquisition mode parameters (`num_acc`, `cycle_time_acc`)

**setup\_kinetic\_mode(num\_cycle, cycle\_time=0.0, num\_acc=1, cycle\_time\_acc=0, num\_prescan=0)**

Switch into the kinetic acquisition mode and set up its parameters.

`num_cycle` is the number of kinetic cycles frames, `cycle_time` is the acquisition period between accum frames, `num_accum` is the number of accumulated frames, `cycle_time_acc` is the accum acquisition period, `num_prescan` is the number of prescans.

**get\_kinetic\_mode\_parameters()**

Return kinetic acquisition mode parameters (`num_cycle`, `cycle_time`, `num_acc`, `cycle_time_acc`, `num_prescan`)

**setup\_fast\_kinetic\_mode**(*num\_acc*, *cycle\_time\_acc*=0.0)

Switch into the fast kinetic acquisition mode and set up its parameters.

*num\_acc* is the number of accumulated frames, *cycle\_time\_acc* is the acquisition period (by default the minimal possible based on exposure and transfer time).

**get\_fast\_kinetic\_mode\_parameters**()

Return fast kinetic acquisition mode parameters (*num\_acc*, *cycle\_time\_acc*)

**setup\_cont\_mode**(*cycle\_time*=0)

Switch into the continuous acquisition mode and set up its parameters.

*cycle\_time* is the acquisition period (by default the minimal possible based on exposure and transfer time).

**get\_cont\_mode\_parameters**()

Return continuous acquisition mode parameters *cycle\_time*

**set\_exposure**(*exposure*)

Set camera exposure

**get\_exposure**()

Get current exposure

**set\_frame\_period**(*frame\_period*)

Set frame acquisition period for the continuous mode

**enable\_frame\_transfer\_mode**(*enable*=True)

Enable frame transfer mode.

For description, see Andor SDK manual.

**is\_frame\_transfer\_enabled**()

Return whether the frame transfer mode is enabled

**get\_cycle\_timings**()

Get acquisition timing.

Return tuple (*exposure*, *accum\_cycle\_time*, *kinetic\_cycle\_time*). In continuous mode, the relevant cycle time is *kinetic\_cycle\_time*.

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (*exposure*, *frame\_period*). Frame period is the rate of frame generation, not of internal frame acquisition (e.g., in accumulator or kinetic mode this is the rate of generating a single accumulated frame, which is *num\_acc* times larger than the internal frame period).

**get\_readout\_time**()

Get frame readout time

**get\_keepclean\_time**()

Get sensor keep-clean time

**set\_read\_mode**(*mode*)

Set camera read mode.

Can be "fvb" (average all image vertically and return it as one row), "single\_track" (read a single row or several rows averaged together), "multi\_track" (read multiple rows or averaged sets of rows), "random\_track" (read several arbitrary lines), or "image" (read a whole image or its rectangular part).

**get\_read\_mode()**

Get the current read mode

**setup\_single\_track\_mode**(*center=0, width=1*)

Switch into the single-track read mode and set up its parameters.

*center* and *width* specify selection of the rows to be averaged together.

**get\_single\_track\_mode\_parameters()**

Return single-track read mode parameters (*center*, *width*)

**setup\_multi\_track\_mode**(*number=1, height=1, offset=0*)

Switch into the multi-track read mode and set up its parameters.

*number* is the number of rows (or row sets) to read, *height* is number of one row set (1 for a single row), *offset* is the distance between the row sets. Return a tuple (*number*, *height*, *offset*, *top*, *gap*), where *top* is the offset of the first row from the top, and *gap* is the gap between the tracks.

**get\_multi\_track\_mode\_parameters()**

Return multi-track read mode parameters (*number*, *height*, *offset*)

**setup\_random\_track\_mode**(*tracks=None*)

Switch into the random-track read mode and set up its parameters.

*tracks* is a list of tuples (*start*, *stop*) specifying track span (*start* are inclusive, *stop* are exclusive, starting from 0). Note that it does not affect the current read mode, which should be set using [set\\_read\\_mode\(\)](#).

**get\_random\_track\_mode\_parameters()**

Return random-track read mode parameters, i.e., the list of track positions

**setup\_image\_mode**(*hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1*)

Switch into the image read mode and set up its parameters.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (*start* are inclusive, *stop* are exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values.

**get\_image\_mode\_parameters()**

Return image read mode parameters, (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*)

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (*start* is inclusive, *stop* is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (*start* is inclusive, *stop* is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**setup\_acquisition**(*mode=None, nframes=None*)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**clear\_acquisition**()

Clear acquisition settings

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**get\_acquisition\_progress**()

Get acquisition progress.

Return tuple (*frames\_done, acc\_done*) with the number of full transferred frames and the number of acquired sub-frames in the current accumulation cycle.

**get\_buffer\_size**()

Get the size of the image ring buffer

**FrameTransferError**

alias of [DefaultFrameTransferError](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name: value*} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {*name: value*}

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (*width, height*); take indexing mode into account

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).



**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fnt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fnt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

**pylablib.devices.Andor.AndorSDK3 module****class** pylablib.devices.Andor.AndorSDK3.**LibraryController**(*lib*)Bases: *LibraryController***close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

pylablib.devices.Andor.AndorSDK3.**restart\_lib**()pylablib.devices.Andor.AndorSDK3.**get\_cameras\_number**()

Get number of connected Andor cameras

**class** pylablib.devices.Andor.AndorSDK3.**AndorSDK3Attribute**(*handle*, *name*, *kind*='auto')Bases: *object*

Andor SDK3 camera attribute.

Allows to query and set values and get additional information. Usually created automatically by a Andor SDK3 camera instance, but could also be created manually.

**Parameters**

- **handle** – Andor SDK3 camera handle
- **pid** – attribute id
- **kind** – attribute kind; can be "float", "int", "str", "bool", "enum", or "comm" (command); can also be "auto" (default), in which case it is obtained from the stored feature table; newer features might be missing, in which case kind needs to be supplied explicitly, or it raises an error

**name**

attribute name

**kind**

attribute kind; can be "float", "int", "str", "bool", "enum", or "comm" (command)

**implemented**

whether attribute is implemented

**Type**

bool

**readable**

whether attribute is readable

**Type**

bool

**writable**

whether attribute is writable

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**is\_command**

whether attribute is a command (same as `kind=="comm"`)

**Type**

bool

**update\_properties()**

Update all attribute properties: implemented, readable, writable, limits

**get\_value(enum\_as\_str=True, not\_implemented\_error=True, default=None)**

Get current value.

If `enum_as_str==True`, return enum values as strings; otherwise, return as indices. If `not_implemented_error==True` and the feature is not implemented, raise [AndorError](#); otherwise, return *default* if it is not implemented.

**set\_value**(*value*, *not\_implemented\_error=True*)

Set current value.

If *not\_implemented\_error==True* and the feature is not implemented, raise [AndorError](#); otherwise, do nothing.

**call\_command**()

Execute the given command

**get\_range**(*enum\_as\_str=True*)

Get allowed range of the given value.

For "int" or "float" values return tuple (min, max) (inclusive); for "enum" return list of possible values (if *enum\_as\_str==True*, return list of string values, otherwise return list of indices). For all other value kinds return None.

**update\_limits**()

Update minimal and maximal attribute limits and return tuple (min, max)

**truncate\_value**(*value*)

Limit value to lie within the allowed range

**class** pylablib.devices.Andor.AndorSDK3.**TDeviceInfo**(*camera\_name*, *camera\_model*, *serial\_number*,  
*firmware\_version*, *software\_version*)

Bases: [tuple](#)

**camera\_model**

**camera\_name**

**firmware\_version**

**serial\_number**

**software\_version**

**class** pylablib.devices.Andor.AndorSDK3.**TMissedFramesStatus**(*skipped*, *overflows*)

Bases: [tuple](#)

**overflows**

**skipped**

**class** pylablib.devices.Andor.AndorSDK3.**TFrameInfo**(*frame\_index*, *timestamp\_dev*, *size*, *pixeltype*,  
*stride*)

Bases: [tuple](#)

**frame\_index**

**pixeltype**

**size**

**stride**

**timestamp\_dev**

**class** `pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera(idx=0)`

Bases: *IBinROICamera*, *IExposureCamera*, *IAttributeCamera*

Andor SDK3 camera.

#### Parameters

**idx** (*int*) – camera index (use `get_cameras_number()` to get the total number of connected cameras)

#### Error

alias of *AndorError*

#### TimeoutError

alias of *AndorTimeoutError*

#### FrameTransferError

alias of *AndorFrameTransferError*

#### `open()`

Open connection to the camera

#### `close()`

Close connection to the camera

#### `is_opened()`

Check if the device is connected

#### `add_attribute(name, kind)`

Add a new attribute which is not currently present in the dictionary.

*kind* can be "float", "int", "str", "bool", "enum", or "comm" (command).

#### `get_attribute(name, update_properties=False, error_on_missing=True)`

Get the camera attribute with the given name.

If `update_properties==True`, automatically update all attribute properties.

#### `get_attribute_value(name, enum_as_str=True, update_properties=False, error_on_missing=True, default=None)`

Get value of an attribute with the given name.

If `update_properties==True`, automatically update all attribute properties before settings. If the value doesn't exist or can not be read and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not None, assume that `error_on_missing==False`.

#### `set_attribute_value(name, value, update_properties=True, error_on_missing=True)`

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If `update_properties==True`, automatically update all attribute properties before settings.

#### `get_all_attribute_values(root="", enum_as_str=True, update_properties=False)`

Get values of all attributes.

If `update_properties==True`, automatically update all attribute properties before settings.

#### `set_all_attribute_values(settings, update_properties=True)`

Set values of all attribute in the given dictionary.

If `update_properties==True`, automatically update all attribute properties before settings.

**call\_command**(*name*)

Execute the given command

**get\_device\_info**()

Get camera info.

Return tuple (camera\_name, camera\_model, serial\_number, firmware\_version, software\_version).

**get\_trigger\_mode**()

Get trigger mode.

Can be "int" (internal), "ext" (external), "software" (software trigger), "ext\_start" (external start), or "ext\_exp" (external exposure).

**set\_trigger\_mode**(*mode*)

Set trigger mode.

Can be "int" (internal), "ext" (external), or "software" (software trigger).

**get\_shutter**()

Get current shutter mode

**set\_shutter**(*mode*)

Set trigger mode.

Can be "open", "closed", or "auto".

**is\_cooler\_on**()

Check if the cooler is on

**set\_cooler**(*on=True*)

Set the cooler on or off

**get\_temperature**()

Get the current camera temperature

**get\_temperature\_setpoint**()

Get current temperature setpoint

**set\_temperature**(*temperature, enable\_cooler=True*)

Change the temperature setpoint.

If enable\_cooler==True, turn the cooler on automatically.

**get\_exposure**()

Get current exposure

**set\_exposure**(*exposure*)

Set camera exposure

**get\_frame\_period**()

Get frame period (time between two consecutive frames in the internal trigger mode)

**set\_frame\_period**(*frame\_period*)

Set frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (exposure, frame\_period).

**is\_metadata\_enabled()**

Check if the metadata enabled

**enable\_metadata(enable=True)**

Enable or disable metadata streaming

**class BufferManager(cam)**

Bases: `object`

Cython-based schedule loop manager.

Runs the loop function and provides callback storage.

**allocate\_buffers(nbuff, size, queued\_buffers=None)**

Allocate and queue buffers.

*queued\_buffers* specifies number of allocated buffers to keep queued at a given time (by default, all of them)

**deallocate\_buffers()**

Deallocated buffers (flushing should be done manually)

**readn(idx, n, size=None, off=0)**

Return *n* buffers starting from *idx*, taking *size* bytes from each

**reset()**

Reset counter (on frame acquisition)

**start\_loop()**

Start loop serving the given buffer manager

**stop\_loop()**

Stop the loop thread

**get\_status()**

Get the current loop status, which is the tuple (acquired,)

**on\_overflow()**

Process buffer overflow event

**new\_overflow()**

**setup\_acquisition(mode='sequence', nframes=100)**

Setup acquisition.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* determines number of frames to acquire in the single mode, or size of the ring buffer in the "sequence" mode (by default, 100).

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as `:meth:`setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**get\_missed\_frames\_status()**

Get missed frames status.

Return tuple (`skipped`, `overflows`) with the number skipped frames (sent from camera to the PC, but not read and overwritten) and number of buffer overflows (events when the frame rate is too for the data transfer, so some unknown number of frames is skipped).

**reset\_overflows\_counter()**

Reset buffer overflows counter

**set\_overflow\_behavior(*behavior*)**

Choose the camera behavior if buffer overflow is encountered when waiting for a new frame.

Can be "error" (raise `AndorFrameTransferError`), "restart" (restart the acquisition), or "ignore" (ignore the overflow, which will cause the wait to time out).

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (`width`, `height`)

**get\_roi()**

Get current ROI.

Return tuple (`hstart`, `hend`, `vstart`, `vend`, `hbin`, `vbin`).

**set\_roi(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*, *hbin=1*, *vbin=1*)**

Set current ROI.

By default, all non-supplied parameters take extreme values. Binning is the same for both axes.

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (`hlim`, `vlim`), where each element is in turn a limit 5-tuple (`min`, `max`, `pstep`, `sstep`, `maxbin`) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning.

Note that the minimal ROI size depends on the current (not just supplied) binning settings. For more accurate results, is it only after setting up the binning.

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {`name`: `value`}

**get\_all\_attributes(*copy=False*)**

Return a dictionary of all available attributes.

If `copy==True`, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).



**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (*acquired*, *unread*, *skipped*, *size*), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(*include=0*)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(*include=0*)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_newest\_image(peek=False, return\_info=False)**

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image(peek=False, return\_info=False)**

Read the oldest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt*, *include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0*, *return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread'*, *nframes=1*, *timeout=20.0*, *error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, *None* (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise *TimeoutError*. If *error\_on\_stopped==True* and the acquisition is not running, raise *Error*; otherwise, simply return *False* without waiting.

**read\_multiple\_images**(*rng=None*, *peek=False*, *missing\_frame='skip'*, *return\_info=False*, *return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but

not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==True, return tuple (frames, infos), where infos is a list of *TFrameInfo* instances describing frame index and frame metadata, which contains timestamp, image size, pixel format, and row stride; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is None. if *return\_rng*==True, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

## pylablib.devices.Andor.Shamrock module

**class** pylablib.devices.Andor.Shamrock.**LibraryController**(lib)

Bases: *LibraryController*

**close**(opid)

Mark device closing.

Return tuple (close\_result, uninit\_result) with the results of the closing and the shutdown. If library does not need to be shut down yet, set uninit\_result=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (init\_result, open\_result, opid) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set init\_result=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

pylablib.devices.Andor.Shamrock.**restart\_lib**()

pylablib.devices.Andor.Shamrock.**list\_spectrographs**()

Return list of serial numbers of all connected Shamrock spectrographs

pylablib.devices.Andor.Shamrock.**get\_spectrographs\_number**()

Get number of connected Shamrock spectrographs

**class** pylablib.devices.Andor.Shamrock.**TDeviceInfo**(serial\_number)

Bases: *tuple*

**serial\_number**

**class** pylablib.devices.Andor.Shamrock.**TOpticalParameters**(focal\_length, angular\_deviation,  
focal\_tilt)

Bases: *tuple*

**angular\_deviation**

**focal\_length****focal\_tilt****class** pylablib.devices.Andor.Shamrock.**TGratingInfo**(*lines, blaze\_wavelength, home, offset*)Bases: [tuple](#)**blaze\_wavelength****home****lines****offset****class** pylablib.devices.Andor.Shamrock.**ShamrockSpectrograph**(*idx=0*)Bases: [IDevice](#)

Shamrock spectrograph.

**Parameters****idx** (*int*) – spectrograph index (starting from 0; use [list\\_spectrographs\(\)](#) to get the list of all connected spectrographs)**Error**alias of [AndorError](#)**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get spectrograph device info.

Return tuple (serial\_number).

**get\_optical\_parameters()**

Get device optical parameters.

Return tuple (focal\_length, angular\_deviation, focal\_tilt).

**get\_gratings\_number()**

Get number of gratings

**get\_grating()**

Get current grating index (counting from 1)

**set\_grating**(*grating, force=False*)

Set current grating (counting from 1)

Call blocks until the grating is exchanged (up to 10-20 seconds). If *force==False* and the current grating index is the same as requested, skip the call; otherwise, call the grating set command regardless (takes about a second in the grating is unchanged).

**get\_grating\_info**(*grating=None*)

Get info of a given grating (by default, current grating).

Return tuple (lines, blaze\_wavelength, home, offset) (blazing wavelength is in nm).

**get\_grating\_offset**(*grating=None*)

Get grating offset (in steps) for a given grating (by default, current grating)

**set\_grating\_offset**(*offset, grating=None*)

Set grating offset (in steps) for a given grating (by default, current grating)

**get\_detector\_offset**()

Get detector offset (in steps)

**set\_detector\_offset**(*offset*)

Set detector offset (in steps)

**get\_turret**()

Get turret

**set\_turret**(*turret*)

Set turret

**is\_wavelength\_control\_present**()

Check if wavelength control is present

**get\_wavelength**()

Get current central wavelength (in m)

**set\_wavelength**(*wavelength*)

Get current central wavelength (in m)

**get\_wavelength\_limits**(*grating=None*)

Get wavelength limits (in m) for a given grating (by default, current grating)

**reset\_wavelength**()

Reset current wavelength to 0 nm

**is\_at\_zero\_order**()

Check if current grating is at zero order

**goto\_zero\_order**()

Set current grating to zero order

**is\_slit\_present**(*slit*)

Check if the slit is present.

*slit* can be either a slit index (starting from 1), or one of the following: "input\_side", "input\_direct", "output\_side", or "output\_direct".

**get\_slit\_width**(*slit*)

Get slit width (in m).

*slit* can be either a slit index (starting from 1), or one of the following: "input\_side", "input\_direct", "output\_side", or "output\_direct".

**set\_slit\_width**(*slit*, *width*)

Set slit width (in m).

*slit* can be either a slit index (starting from 1), or one of the following: "input\_side", "input\_direct", "output\_side", or "output\_direct".

**reset\_slit**(*slit*)

Reset slit to the default width (10 um).

*slit* can be either a slit index (starting from 1), or one of the following: "input\_side", "input\_direct", "output\_side", or "output\_direct".

**is\_shutter\_present**()

Check if the shutter is present

**get\_shutter**()

Get shutter mode.

Can return "closed", "opened", "bnc", or "not\_set".

**is\_shutter\_mode\_possible**(*mode*)

Check if the shutter mode ("closed", "opened", or "bnc") is supported

**set\_shutter**(*mode*)

Set shutter mode ("closed" or "opened")

**is\_filter\_present**()

Check if the filter is present

**get\_filter**()

Get current filter

**set\_filter**(*flt*)

Set current filter

**get\_filter\_info**(*flt*)

Get info of the given filter

**reset\_filter**()

Reset filter to default position

**is\_flipper\_present**(*flipper*)

Check if the flipper is present.

*flipper* can be a flipper index (starting from 1), "input", or "output".

**get\_flipper\_port**(*flipper*)

Get flipper port.

*flipper* can be a flipper index (starting from 1), "input", or "output". Return either "direct" or "side".

**set\_flipper\_port**(*flipper*, *port*)

Set flipper port.

*flipper* can be a flipper index (starting from 1), "input", or "output". Port can be "direct" or "side".

**reset\_flipper**(*flipper*)

Reset flipper to the default state.

*flipper* can be a flipper index (starting from 1), "input", or "output".

**is\_iris\_present**(*iris*)

Check if the iris is present

**get\_iris\_width**(*iris*)

Get current iris width (0 to 100)

**set\_iris\_width**(*iris*, *width*)

Set current iris width (0 to 100)

**is\_focus\_mirror\_present**()

Check if the focus mirror is present

**get\_focus\_mirror\_position**()

Get current focus mirror position

**set\_focus\_mirror\_position**(*position*)

Set current focus mirror position

**get\_focus\_mirror\_position\_max**()

Get maximal focus mirror position

**reset\_focus\_mirror**()

Reset focus mirror position

**is\_accessory\_present**()

Check if the accessory is present

**get\_accessory\_state**(*line*)

Get current accessory state on a given line (1 or 2)

**set\_accessory\_state**(*line*, *state*)

Set current accessory state (0 or 1) on a given line (1 or 2)

**get\_pixel\_width**()

Get current set detector pixel width (in m)

**set\_pixel\_width**(*width*)

Set current detector pixel width (in m)

**get\_number\_pixels**()

Get current set detector number of pixels

**set\_number\_pixels**(*number*)

Set current detector number of pixels

**setup\_pixels\_from\_camera**(*cam*)

Setup detector parameters (number of pixels, pixel width) from the camera

**get\_calibration**()

Get wavelength calibration.

Return numpy array which specifies wavelength (in m) corresponding to each pixel. Prior to calling this method, the total number of pixels and the pixel width of the sensor should be set up using the corresponding methods ([\*set\\_number\\_pixels\(\)\*](#) and [\*set\\_pixel\\_width\(\)\*](#), or [\*setup\\_pixels\\_from\\_camera\(\)\*](#) to set both parameters using and AndorSDK2 camera instance)



**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**pylablib.devices.Andor.atcore\_features module****pylablib.devices.Andor.base module****exception pylablib.devices.Andor.base.AndorError**

Bases: [DeviceError](#)

Generic Andor error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception pylablib.devices.Andor.base.AndorTimeoutError**

Bases: [AndorError](#)

Andor timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Andor.base.**AndorFrameTransferError**

Bases: [AndorError](#)

Andor frame transfer error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Andor.base.**AndorNotSupportedError**

Bases: [AndorError](#)

Option not supported error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## Module contents

### pylablib.devices.Arcus package

#### Submodules

#### pylablib.devices.Arcus.base module

**exception** pylablib.devices.Arcus.base.**ArcusError**

Bases: [DeviceError](#)

Generic Arcus error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Arcus.base.**ArcusBackendError**(exc)

Bases: [ArcusError](#), [DeviceBackendError](#)

Generic Arcus backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## pylablib.devices.Arcus.performax module

pylablib.devices.Arcus.performax.get\_usb\_device\_info(deviceid)

Get info for the given device index (starting from 0).

Return tuple (index, serial, model, desc, vid, pid).

pylablib.devices.Arcus.performax.list\_usb\_performax\_devices()

List all performax devices.

Return list of tuples (index, serial, model, desc, vid, pid), one per device.

**class** pylablib.devices.Arcus.performax.GenericPerformaxStage(idx=0, conn=None)

Bases: [IMultiaxisStage](#)

Generic Arcus Performax translation stage.

### Parameters

- **idx** (*int*) – stage index; if using a USB connection, specifies a USB device index; if using RS485 connection, specifies device index on the bus
- **conn** – if not *None*, defines a connection to RS485 connection. Usually (e.g., for USB-to-RS485 adapters) this is a serial connection, which either a name (e.g., "COM1"), or a tuple (name, baudrate) (e.g., ("COM1", 9600)); if *conn* is *None*, assume direct USB connection and use the manufacturer-provided DLL

### Error

alias of [ArcusError](#)

**open()**

Open the connection to the stage

**close()**

Close the connection to the stage

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get the device info

**query(comm)**

Send a query to the stage and return the reply

**get\_device\_number()**

Get the device number used in RS-485 communications.

Usually it is a string with the format similar to "4EX00".

**set\_device\_number**(*number*, *store=True*)

Get the device number used in RS-485 communications.

*number* can be either a full device id (e.g., "4EX00"), or a single number between 0 and 99. In order for the change to take effect, the device needs to be power-cycled. If *store==True*, automatically store settings to the memory; otherwise, the settings will be lost unless [store\\_defaults\(\)](#) is called at some point before the power-cycle.

**store\_defaults**()

Store some of the settings to the memory as defaults.

Applies to device number, baudrate, limit error behavior, polarity, and some other settings.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**class** pylablib.devices.Arcus.performax.**Performax4EXStage**(*idx=0*, *conn=None*, *enable=True*)

Bases: [GenericPerformaxStage](#)

Arcus Performax 4EX/4ET translation stage.

**Parameters**

- **idx** (*int*) – stage index; if using a USB connection, specifies a USB device index; if using RS485 connection, specifies device index on the bus
- **conn** – if not `None`, defines a connection to RS485 connection. Usually (e.g., for USB-to-RS485 adapters) this is a serial connection, which either a name (e.g., "COM1"), or a tuple (name, baudrate) (e.g., ("COM1", 9600)); if *conn* is `None`, assume direct USB connection and use the manufacturer-provided DLL
- **enable** – if `True`, enable all axes on startup

**get\_baudrate()**

Get current baud rate

**set\_baudrate(baudrate, store=True)**

Set current baud rate.

Acceptable values are 9600 (default), 19200, 38400, 57600, and 115200. In order for the change to take effect, the device needs to be power-cycled. If `store==True`, automatically store settings to the memory; otherwise, the settings will be lost unless `store_defaults()` is called at some point before the power-cycle.

**enable\_absolute\_mode(enable=True)**

Set absolute motion mode

**enable\_limit\_errors(enable=True, autoclear=True)**

Enable limit errors.

If on, reaching limit switch on an axis puts it into an error state, which immediately stops this and all other axes; any further motion command on this axis will raise an error (it is still possible to restart motion on other axes); the axis motion can only be resumed by calling `clear_limit_error()`. If off, the limited axis still stops, but the other axes are unaffected. If `autoclear==True` and `enable==False`, also clear the current limit errors on all axes.

**limit\_errors\_enabled()**

Check if global limit errors are enabled.

If on, reaching limit switch on an axis puts it into an error state, which immediately stops this and all other axes; any further motion command on this axis will raise an error (it is still possible to restart motion on other axes); the axis motion can only be resumed by calling `clear_limit_error()`. If off, the limited axis still stops, but the other axes are unaffected.

**is\_enabled(axis='all')**

Check if the axis output is enabled

**enable\_axis(axis='all', enable=True)**

Enable axis output.

If the output is disabled, the steps are generated by the controller, but not sent to the motors.

**get\_position(axis='all')**

Get the current axis pulse position

**set\_position\_reference(axis, position=0)**

Set the current axis pulse position as a reference.

Re-calibrate the pulse position counter so that the current position is set as *position* (0 by default).

**get\_encoder(axis='all')**

Get the current axis encoder value

**set\_encoder\_reference**(*axis*, *position*=0)

Set the current axis encoder value as a reference.

Re-calibrate the encoder counter so that the current position is set as *position* (0 by default).

**move\_to**(*axis*, *position*)

Move a given axis to a given position

**move\_by**(*axis*, *steps*=1)

Move a given axis for a given number of steps

**jog**(*axis*, *direction*)

Jog a given axis in a given direction.

*direction* can be either "-" (negative) or "+" (positive). The motion continues until it is explicitly stopped, or until a limit is hit.

**stop**(*axis*='all', *immediate*=False)

Stop motion of a given axis.

If *immediate*==True make an abrupt stop; otherwise, slow down gradually.

**home**(*axis*, *direction*, *home\_mode*)

Home the given axis using a given home mode.

*direction* can be "+" or "-" The mode can be "only\_home\_input", "only\_home\_input\_lowspeed", "only\_limit\_input", "only\_zidx\_input", or "home\_and\_zidx\_input". For meaning, see Arcus PMX manual.

**get\_global\_speed**()

Get the global speed setting (in Hz); overridden by a non-zero axis speed

**get\_axis\_speed**(*axis*='all')

Get the individual axis speed setting (in Hz); 0 means that the global speed is used

**set\_global\_speed**(*speed*)

Set the global speed setting (in Hz); overridden by a non-zero axis speed

**set\_axis\_speed**(*axis*, *speed*)

Set the individual axis speed setting (in Hz); 0 means that the global speed is used

**get\_current\_axis\_speed**(*axis*='all')

Get the instantaneous speed (in Hz)

**get\_status\_n**(*axis*='all')

Get the axis status as an integer

**get\_status**(*axis*='all')

Get the axis status as a set of string descriptors

**is\_moving**(*axis*='all')

Check if a given axis is moving

**wait\_move**(*axis*, *timeout*=None, *period*=0.05)

Wait until motion is done

**check\_limit\_error**(*axis*='all')

Check if the axis hit limit errors.

Return "" (not errors), "+" (positive limit error) or "-" (negative limit error).

**clear\_limit\_error**(*axis='all'*)

Clear axis limit errors

**get\_analog\_input**(*channel*)

Get voltage (in V) at a given input (starting with 1)

**get\_digital\_input**(*channel*)

Get value (0 or 1) at a given digital input (1 through 8)

**get\_digital\_input\_register**()

Get all 8 digital inputs as a single 8-bit integer

**get\_digital\_output**(*channel*)

Get value (0 or 1) at a given digital output (1 through 8)

**get\_digital\_output\_register**()

Get all 8 digital inputs as a single 8-bit integer

**set\_digital\_output**(*channel, value*)

Set value (0 or 1) at a given digital output (1 through 8)

**set\_digital\_output\_register**(*value*)

Set all 8 digital inputs as a single 8-bit integer

**Error**

alias of [ArcusError](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection to the stage

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_info**()

Get the device info

**get\_device\_number**()

Get the device number used in RS-485 communications.

Usually it is a string with the format similar to "4EX00".

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection to the stage

**query(comm)**

Send a query to the stage and return the reply

**remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_number(number, store=True)**

Get the device number used in RS-485 communications.

*number* can be either a full device id (e.g., "4EX00"), or a single number between 0 and 99. In order for the change to take effect, the device needs to be power-cycled. If *store==True*, automatically store settings to the memory; otherwise, the settings will be lost unless [store\\_defaults\(\)](#) is called at some point before the power-cycle.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**store\_defaults()**

Store some of the settings to the memory as defaults.

Applies to device number, baudrate, limit error behavior, polarity, and some other settings.

**class** `pylablib.devices.Arcus.performax.Performax2EXStage(idx=0, conn=None, enable=True)`

Bases: [Performax4EXStage](#)

Arcus Performax 2EX/2ED translation stage.

**Parameters**

- **idx** (*int*) – stage index; if using a USB connection, specifies a USB device index; if using RS485 connection, specifies device index on the bus
- **conn** – if not *None*, defines a connection to RS485 connection. Usually (e.g., for USB-to-RS485 adapters) this is a serial connection, which either a name (e.g., "COM1"), or a tuple (name, baudrate) (e.g., ("COM1", 9600)); if *conn* is *None*, assume direct USB connection and use the manufacturer-provided DLL
- **enable** – if *True*, enable all axes on startup



**Error**

alias of [ArcusError](#)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**check\_limit\_error(axis='all')**

Check if the axis hit limit errors.

Return "" (not errors), "+" (positive limit error) or "-" (negative limit error).

**clear\_limit\_error(axis='all')**

Clear axis limit errors

**close()**

Close the connection to the stage

**enable\_absolute\_mode(enable=True)**

Set absolute motion mode

**enable\_axis(axis='all', enable=True)**

Enable axis output.

If the output is disabled, the steps are generated by the controller, but not sent to the motors.

**enable\_limit\_errors(enable=True, autoclear=True)**

Enable limit errors.

If on, reaching limit switch on an axis puts it into an error state, which immediately stops this and all other axes; any further motion command on this axis will raise an error (it is still possible to restart motion on other axes); the axis motion can only be resumed by calling [clear\\_limit\\_error\(\)](#). If off, the limited axis still stops, but the other axes are unaffected. If `autoclear==True` and `enable==False`, also clear the current limit errors on all axes.

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_analog\_input(channel)**

Get voltage (in V) at a given input (starting with 1)

**get\_axis\_speed(axis='all')**

Get the individual axis speed setting (in Hz); 0 means that the global speed is used

**get\_baudrate()**

Get current baud rate

**get\_current\_axis\_speed(axis='all')**

Get the instantaneous speed (in Hz)

**get\_device\_info()**

Get the device info

**get\_device\_number()**

Get the device number used in RS-485 communications.

Usually it is a string with the format similar to "4EX00".

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_digital\_input**(*channel*)

Get value (0 or 1) at a given digital input (1 through 8)

**get\_digital\_input\_register**()

Get all 8 digital inputs as a single 8-bit integer

**get\_digital\_output**(*channel*)

Get value (0 or 1) at a given digital output (1 through 8)

**get\_digital\_output\_register**()

Get all 8 digital inputs as a single 8-bit integer

**get\_encoder**(*axis='all'*)

Get the current axis encoder value

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_global\_speed**()

Get the global speed setting (in Hz); overridden by a non-zero axis speed

**get\_position**(*axis='all'*)

Get the current axis pulse position

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status**(*axis='all'*)

Get the axis status as a set of string descriptors

**get\_status\_n**(*axis='all'*)

Get the axis status as an integer

**home**(*axis, direction, home\_mode*)

Home the given axis using a given home mode.

*direction* can be "+" or "-" The mode can be "only\_home\_input", "only\_home\_input\_lowspeed", "only\_limit\_input", "only\_zidx\_input", or "home\_and\_zidx\_input". For meaning, see Arcus PMX manual.

**is\_enabled**(*axis='all'*)

Check if the axis output is enabled

**is\_moving**(*axis='all'*)

Check if a given axis is moving

**is\_opened**()

Check if the device is connected

**jog**(*axis, direction*)

Jog a given axis in a given direction.

*direction* can be either "-" (negative) or "+" (positive). The motion continues until it is explicitly stopped, or until a limit is hit.

**limit\_errors\_enabled**()

Check if global limit errors are enabled.

If on, reaching limit switch on an axis puts it into an error state, which immediately stops this and all other axes; any further motion command on this axis will raise an error (it is still possible to restart motion on other axes); the axis motion can only be resumed by calling [clear\\_limit\\_error\(\)](#). If off, the limited axis still stops, but the other axes are unaffected.

**move\_by**(*axis, steps=1*)

Move a given axis for a given number of steps

**move\_to**(*axis, position*)

Move a given axis to a given position

**open**()

Open the connection to the stage

**query**(*comm*)

Send a query to the stage and return the reply

**remap\_axes**(*mapping, accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_axis\_speed**(*axis, speed*)

Set the individual axis speed setting (in Hz); 0 means that the global speed is used

**set\_baudrate**(*baudrate, store=True*)

Set current baud rate.

Acceptable values are 9600 (default), 19200, 38400, 57600, and 115200. In order for the change to take effect, the device needs to be power-cycled. If *store==True*, automatically store settings to the memory; otherwise, the settings will be lost unless [store\\_defaults\(\)](#) is called at some point before the power-cycle.

**set\_device\_number**(*number, store=True*)

Get the device number used in RS-485 communications.

*number* can be either a full device id (e.g., "4EX00"), or a single number between 0 and 99. In order for the change to take effect, the device needs to be power-cycled. If *store==True*, automatically store settings to the memory; otherwise, the settings will be lost unless [store\\_defaults\(\)](#) is called at some point before the power-cycle.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_digital\_output**(*channel*, *value*)

Set value (0 or 1) at a given digital output (1 through 8)

**set\_digital\_output\_register**(*value*)

Set all 8 digital inputs as a single 8-bit integer

**set\_encoder\_reference**(*axis*, *position*=0)

Set the current axis encoder value as a reference.

Re-calibrate the encoder counter so that the current position is set as *position* (0 by default).

**set\_global\_speed**(*speed*)

Set the global speed setting (in Hz); overridden by a non-zero axis speed

**set\_position\_reference**(*axis*, *position*=0)

Set the current axis pulse position as a reference.

Re-calibrate the pulse position counter so that the current position is set as *position* (0 by default).

**stop**(*axis*='all', *immediate*=False)

Stop motion of a given axis.

If *immediate*==True make an abrupt stop; otherwise, slow down gradually.

**store\_defaults**()

Store some of the settings to the memory as defaults.

Applies to device number, baudrate, limit error behavior, polarity, and some other settings.

**wait\_move**(*axis*, *timeout*=None, *period*=0.05)

Wait until motion is done

**class** pylablib.devices.Arcus.performax.**PerformaxDMXJSASTage**(*idx*=0, *conn*=None, *enable*=True, *autoclear*=True)

Bases: [GenericPerformaxStage](#)

Arcus Performax DMX-J-SA translation stage.

#### Parameters

- **idx** (*int*) – stage index; if using a USB connection, specifies a USB device index; if using RS485 connection, specifies device index on the bus
- **conn** – if not None, defines a connection to RS485 connection. Usually (e.g., for USB-to-RS485 adapters) this is a serial connection, which either a name (e.g., "COM1"), or a tuple (*name*, *baudrate*) (e.g., ("COM1", 9600)); if *conn* is None, assume direct USB connection and use the manufacturer-provided DLL
- **enable** – if True, enable all axes on startup
- **autoclear** – if True, automatically clear limit error before the motion start

**enable\_absolute\_mode**(*enable*=True)

Set absolute motion mode

**is\_enabled**()

Check if the output is enabled

**enable\_axis**(*enable=True*)

Enable output.

If the output is disabled, the steps are generated by the controller, but not sent to the motors.

**get\_position**()

Get the current pulse position

**set\_position\_reference**(*position=0*)

Set the current pulse position as a reference.

Re-calibrate the pulse position counter so that the current position is set as *position* (0 by default).

**move\_to**(*position*)

Move to a given position

**move\_by**(*steps=1*)

Move for a given number of steps

**jog**(*direction*)

Jog in a given direction.

*direction* can be either "-" (negative) or "+" (positive). The motion continues until it is explicitly stopped, or until a limit is hit.

**stop**(*immediate=False*)

Stop motion.

If *immediate==True* make an abrupt stop; otherwise, slow down gradually.

**home**(*direction, home\_mode*)

Home using a given home mode.

*direction* can be "+" or "-" The mode can be "only\_home\_input", "only\_home\_input\_lowspeed", or "only\_limit\_input". For meaning, see Arcus PMX manual.

**get\_axis\_speed**()

Get the speed setting (in Hz)

**set\_axis\_speed**(*speed*)

Set the speed setting (in Hz)

**get\_status\_n**()

Get the status as an integer

**get\_status**()

Get the status as a set of string descriptors

**is\_moving**()

Check if motor is moving

**wait\_move**(*timeout=None, period=0.05*)

Wait until motion is done

**check\_limit\_error**()

Check if the motor hit limit errors.

Return "" (not errors), "+" (positive limit error) or "-" (negative limit error).

**clear\_limit\_error()**

Clear limit error

**get\_digital\_input(channel)**

Get value (0 or 1) at a given digital input (1 through 5)

**get\_digital\_input\_register()**

Get all 5 digital inputs as a single 5-bit integer

**get\_digital\_output(channel)**

Get value (0 or 1) at a given digital output (1 through 2)

**get\_digital\_output\_register()**

Get all 2 digital outputs as a single 2-bit integer

**Error**

alias of [\*ArcusError\*](#)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the connection to the stage

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_device\_info()**

Get the device info

**get\_device\_number()**

Get the device number used in RS-485 communications.

Usually it is a string with the format similar to "4EX00".

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection to the stage

**query(comm)**

Send a query to the stage and return the reply

**remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_number(number, store=True)**

Get the device number used in RS-485 communications.

*number* can be either a full device id (e.g., "4EX00"), or a single number between 0 and 99. In order for the change to take effect, the device needs to be power-cycled. If *store==True*, automatically store settings to the memory; otherwise, the settings will be lost unless [store\\_defaults\(\)](#) is called at some point before the power-cycle.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**set\_digital\_output(channel, value)**

Set value (0 or 1) at a given digital output (1 through 2)

**store\_defaults()**

Store some of the settings to the memory as defaults.

Applies to device number, baudrate, limit error behavior, polarity, and some other settings.

**set\_digital\_output\_register(value)**

Set all 2 digital inputs as a single 2-bit integer

## Module contents

### pylablib.devices.Arduino package

#### Submodules

#### pylablib.devices.Arduino.base module

**exception** pylablib.devices.Arduino.base.ArduinoErrorBases: [DeviceError](#)

Generic Arduino devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Arduino.base.**ArduinoBackendError**(*exc*)

Bases: [ArduinoError](#), [DeviceBackendError](#)

Generic Arduino backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Arduino.base.**IArduinoDevice**(*port*, *rate*=9600, *timeout*=10.0, *term\_write*='\n',  
*term\_read*='\n', *flush\_before\_op*=True, *dtrrts*=True)

Bases: [ICommBackendWrapper](#)

Generic Arduino device.

**Parameters**

- **port** – serial port name
- **rate** – baud rate
- **timeout** – default communication timeout
- **term\_write** – default write terminating character (automatically appended on every sent message)
- **term\_read** – default read terminating character (used to determine when the incoming message is received completely)
- **flush\_before\_op** – if True (default), automatically flush input buffer on comm/query
- **dtrrts** – determines whether to use DTR/RTS signals for communication; generally, should be set to True on newer boards (e.g., Leonardo) and to False on older boards (e.g., Uno); settings `dtrrts=True` on older boards leads to the board reset upon connection, and settings `dtrrts=False` on newer boards leads to the communications getting frozen

**Error**

alias of [ArduinoError](#)

**reopen()**

Close and reopen the device connection

**reset\_board()**

Reset the board by pulsing the DTR and RTS lines

**comm**(*comm*, *timeout*=None, *flush*=False, *flush\_delay*=0.02)

Send a device command.

If *timeout* is not None, it specifies a custom timeout for the operation. If `flush==True`, then wait for *flush\_delay* seconds after the write and read everything returned by the device.



**query**(*query*, *timeout=None*, *query\_delay=0*, *flush=False*, *flush\_delay=0.02*)

Send a device query and return the reply.

If *timeout* is not *None*, it specifies a custom timeout for the reply read operation. If *query\_delay*>0, it specifies the delay between write and subsequent read attempt. If *flush==True*, then wait for *flush\_delay* seconds after the write and read everything returned by the device.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Attocube package

#### Submodules

#### pylablib.devices.Attocube.anc300 module

`pylablib.devices.Attocube.anc300.muxaxis(*args, **kwargs)`

`class pylablib.devices.Attocube.anc300.TDeviceInfo(serial, version)`

Bases: `tuple`

**serial**

**version**

`class pylablib.devices.Attocube.anc300.ANC300(conn, backend='auto', pwd='123456')`

Bases: `ICommBackendWrapper`, `IMultiaxisStage`

Attocube ANC300 controller.

#### Parameters

- **conn** – connection parameters; for Ethernet connection is a tuple (`addr`, `port`), a string "`addr:port`", or a string "`addr`" (default port 7240 us assumed)
- **backend** (`str`) – communication backend; by default, try to determine from the communication parameters
- **pwd** (`str`) – connection password for Ethernet connection (default is "123456")

#### Error

alias of `AttocubeError`

#### `open()`

Open the connection to the stage

#### `query(msg)`

Send a query to the stage and return the reply

#### `update_available_axes()`

Update the list of available axes.

Need to call only if the hardware configuration of the ANC module has changed.

#### `get_device_info()`

Get the device info of the controller board: (`serial`, `version`)

#### `get_axis_serial(axis='all')`

Get serial number of the controller board

#### `set_mode(axis='all', mode='stp')`

Set axis mode.

`axis` is either an axis index (starting from 1), or "all" (all axes). `mode` can be "gnd" (ground), "stp" (step), "cap" (measure capacitance, then ground), "offs" (offset only, no stepping), "stp+" (offset with added stepping waveform), "stp-" (offset with subtracted stepping). Note that not all modes are supported

by all modules: ANM150 doesn't support offset voltage ("offs", "stp+", "stp-" modes), ANM200 doesn't support stepping ("stp", "stp+", "stp-" modes).

**get\_mode**(*axis*='all')

Get axis mode.

*axis* is either an axis index (starting from 1), or "all" (all axes). See [set\\_mode\(\)](#) for the description of the modes.

**is\_enabled**(*axis*='all')

Check if the axis is enabled

**enable\_axis**(*axis*='all', *mode*='stp')

Enable specific axis (set to step mode)

**disable\_axis**(*axis*='all')

Disable specific axis (set to ground mode)

**measure\_capacitance**(*axis*='all', *wait*=True)

Measure axis capacitance; finish in the GND mode.

If *wait*==True, wait until the capacitance measurement is finished (takes about a second per axis).

**get\_voltage**(*axis*='all')

Get axis step amplitude in Volts

**set\_voltage**(*axis*, *voltage*)

Set axis step amplitude in Volts

**get\_offset**(*axis*='all')

Get axis offset voltage in Volts

**set\_offset**(*axis*, *voltage*)

Set axis offset voltage in Volts

**get\_output**(*axis*='all')

Get axis current output voltage in Volts

**get\_frequency**(*axis*='all')

Get axis step frequency in Hz

**set\_frequency**(*axis*, *freq*)

Set axis step frequency in Hz

**get\_capacitance**(*axis*='all', *measure*=False)

Get capacitance measurement on the axis.

If *measure*==True, re-measure axis capacitance (takes about a second); otherwise, get the last measurement value.

**get\_voltage\_pattern**(*axis*, *kind*)

Get axis voltage pattern.

*kind* be either "up" for up pattern or "down" for down pattern. The pattern is a numpy array of 256 numbers from 0 to 255 corresponding to the output voltage from 0 to the axis voltage. This pattern is output (repeatedly) for each step. The default is a simple linear ramp.

**set\_voltage\_pattern**(*axis, kind, pattern=None*)

Set axis voltage pattern.

*kind* be either "up" for up pattern or "down" for down pattern. The pattern is an array of 256 numbers from 0 to 255 corresponding to the output voltage from 0 to the axis voltage. This pattern is output (repeatedly) for each step. The default is a simple linear ramp, which is set if *pattern* is *None*.

**get\_trigger\_input**(*axis='all'*)

Get trigger input lines for the given axis.

Return tuple (*up*, *down*) with values for up and down step triggers, which can be either integer with the trigger line number, or "off" if the trigger is off.

**set\_trigger\_input**(*axis, up=None, down=None*)

Set trigger input lines for the given axis.

*up* and *down* are can be integer with the trigger line number, "off" if the trigger is off, or *None* (keep the value unchanged).

**get\_external\_input\_modes**(*axis='all'*)

Get external BNC input modes.

Return tuple (*acin*, *dcin*) indicating whether AC-IN and DC-IN channels are enabled.

**set\_external\_input\_modes**(*axis, acin=None, dcin=None*)

Enable or disable external BNC inputs.

*acin* and *dcin* are can be boolean indicating if the corresponding input is enabled, or *None* (keep the value unchanged).

**get\_axis\_correction**(*axis*)

Get axis correction factor.

The factor is automatically applied when the motion is in the negative direction.

**set\_axis\_correction**(*axis, factor=1.0*)

Set axis correction factor.

The factor is automatically applied when the motion is in the negative direction.

**jog**(*axis, direction*)

Jog continuously in the given direction ("+" or "-").

The motion will continue until another move or stop command is called.

**move\_by**(*axis, steps=1*)

Move a given axis for a given number of steps

**wait\_move**(*axis, timeout=30.0*)

Wait for a given axis to stop moving.

If the motion is not finished after *timeout* seconds, raise a backend error.

**is\_moving**(*axis*)

Check if a given axis is moving

**stop**(*axis='all'*)

Stop motion of a given axis

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**pylablib.devices.Attocube.anc350 module**

`pylablib.devices.Attocube.anc350.get_usb_devices_number()`

Get the number of controllers connected via USB

**class** `pylablib.devices.Attocube.anc350.ANC350(conn=0, timeout=5.0)`

Bases: *ICommBackendWrapper*, *IMultiaxisStage*

Attocube ANC350 controller.

**Parameters**

- **conn** – connection parameters - index of the Attocube ANC350 in the system (for a single controller leave 0)
- **timeout** (*float*) – default operation timeout

**Error**

alias of *AttocubeError*

**class** `Telegram(opcode, address, index, data, corr_number)`

Bases: *tuple*

**address**

**corr\_number**

**data**

**index**

**opcode**

**class** `Reply(address, index, reason, data)`

Bases: *tuple*

**address**

**data**

**index**

**reason**

**check\_tell**(*timeout=0.01*)

Check for queued TELL (periodic value update) commands

**set\_value**(*address, index, value, ack=False*)

Set device value at the given address and index.

If `ack==True`, request ACK responds and return its value; otherwise, return immediately after set.

**get\_value**(*address, index, as\_int=True*)

Get device value at the given address and index.

If `as_int==True`, convert the result into a signed integer; otherwise return raw byte string.

**enable\_updates**(*enabled=True*)

Enable or disable periodic TELL updates

**get\_hardware\_id()**

Return device HWID (by default -1)

**set\_hardware\_id(*hwid*, *persist=False*)**

Set device HWID (can be used to identify different devices).

If *persist==True*, the value persists after power cycling.

**is\_connected(*axis='all'*)**

Check if axis is connected

**is\_enabled(*axis='all'*)**

Check if axis is enabled

**enable\_axis(*axis='all'*, *enabled=True*)**

Enable a specific axis or all axes

**disable\_axis(*axis='all'*)**

Disable a specific axis or all axes

**is\_moving(*axis='all'*)**

Move a given axis for a given number of steps

**check\_limit(*axis='all'*)**

Check if the end of travel has been reached.

Return *None* if no limits are reached, "fwd" if forward limit is reached, "bwd" if backward limit is reached, or "both" if both are reached together (normally shouldn't happen).

**get\_status\_n(*axis='all'*)**

Get numerical status of the axis.

For details, see ANC350 protocol.

```
status_bits = [(1, 'running'), (2, 'limit'), (256, 'sens_err'), (1024,
'sens_disconn'), (2048, 'ref_valid')]
```

**get\_status(*axis='all'*)**

Get device status.

Return list of status strings, which can include "running" (axis is moving), "limit" (one of the limits is reached), "sens\_err" (sensor error), "sens\_disconn" (sensor disconnected), or "ref\_valid" (reference is valid).

**get\_target\_position(*axis='all'*)**

Get the target position for the given axis (the position towards which it is moving)

**get\_precision(*axis='all'*)**

Get the axis precision in m (used for checking if the target is reached)

**set\_precision(*axis='all'*, *precision=1e-06*)**

Set the axis precision in m (used for checking if the target is reached)

**is\_target\_reached(*axis='all'*, *precision=None*)**

Check if the target position is reached.

If *precision* is not *None*, it sets final position tolerance (in m).

**get\_sensor\_voltage()**

Get position sensor voltage in Volts

**set\_sensor\_voltage**(*voltage*)

Set position sensor voltage in Volts

**get\_voltage**(*axis='all'*)

Get axis step voltage in Volts

**set\_voltage**(*axis, voltage*)

Set axis step voltage in Volts

**get\_offset**(*axis='all'*)

Get axis offset voltage in Volts

**set\_offset**(*axis, voltage*)

Set axis offset voltage in Volts

**get\_frequency**(*axis='all'*)

Get axis step frequency in Hz

**set\_frequency**(*axis, freq*)

Set axis step frequency in Hz

**get\_capacitance**(*axis='all', measure=False, delay=0.5*)

Get axis capacitance in F.

If *measure==True*, initialize the measurement and get the result after the measurement *delay*. Otherwise, return the last measured value.

**get\_position**(*axis='all'*)

Get axis position (in m)

**move\_to**(*axis, position, precision=None*)

Move to target position (in m).

If *precision* is not *None*, it sets final position tolerance.

**move\_by**(*axis, dist*)

Move along a given axis by a given distance (in m)

**move\_by\_steps**(*axis, steps=1, delay=0*)

Move along a given axis by a given number of steps

**wait\_move**(*axis, precision=1e-06, timeout=10.0, period=0.01*)

Wait for a given axis to stop moving or to reach target position.

If the motion is not finished after *timeout* seconds, raise a backend error. Precision sets the final positioning precision (in m).

**stop**(*axis='all'*)

Stop motion of a given axis

**jog**(*axis, direction*)

Jog a given axis in a given direction.

*direction* can be either "-" (negative) or "+" (positive). The motion continues until it is explicitly stopped, or until a limit is hit.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.



**close()**

Close the backend

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## pylablib.devices.Attocube.base module

**exception** pylablib.devices.Attocube.base.**AttocubeError**

Bases: *DeviceError*

Generic Attocube error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Attocube.base.**AttocubeBackendError**(*exc*)

Bases: *AttocubeError*, *DeviceBackendError*

Attocube backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## Module contents

### pylablib.devices.Basler package

#### Submodules

### pylablib.devices.Basler.pylon module

**class** pylablib.devices.Basler.pylon.**LibraryController**(*lib*)

Bases: *LibraryController*

**close**(*opid*)

Mark device closing.

Return tuple (close\_result, uninit\_result) with the results of the closing and the shutdown. If library does not need to be shut down yet, set uninit\_result=None

**get\_opened\_num()**

Get number of opened devices

**open()**

Mark device opening.

Return tuple (init\_result, open\_result, opid) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set init\_result=None

**preinit()**

Pre-initialize the library, if it hasn't been done already

**shutdown()**

Close all opened connections and shutdown the library

**temp\_open()**

Context for temporarily opening a new device connection

`pylablib.devices.Basler.pylon.restart_lib()`

**class** `pylablib.devices.Basler.pylon.TCameraInfo`(*name, model, serial, devclass, devversion, vendor, friendly\_name, user\_name, props*)

Bases: `tuple`

**devclass**

**devversion**

**friendly\_name**

**model**

**name**

**props**

**serial**

**user\_name**

**vendor**

`pylablib.devices.Basler.pylon.get_device_info(index)`

Get Pylon camera info for a camera with the given index

`pylablib.devices.Basler.pylon.list_cameras(desc=True)`

List all cameras available through Basler Pylon interface

If `desc==True`, return complete camera descriptions; otherwise, simply return the names.

`pylablib.devices.Basler.pylon.get_cameras_number()`

Get number of connected Basler Pylon cameras

**class** `pylablib.devices.Basler.pylon.BaslerPylonAttribute`(*node, full\_name=None*)

Bases: `object`

Object representing an Pylon GenAPI attribute.

Allows to query and set values and get additional information. Usually created automatically by an [BaslerPylonCamera](#) instance.

#### Parameters

- **node** – pylon GenApi node handler
- **full\_name** – if supplied, attribute's full name, including the tree structure

**name**

attribute name

**kind**

attribute kind; can be "int", "float", "bool", "enum", "str", "command", "category", or "unknown"

**display\_name**

attribute display name (short description name)

**tooltip**

longer attribute description

**description**

full attribute description (usually, same as *tooltip*)

**visibility**

attribute visibility; can be "simple", "intermediate", "advanced", "invisible", or "unknown"

**access**

attribute access level; can be "read\_only", "write\_only", "read\_write", "na" (not applicable, e.g., command), or "not\_implemented"

**readable**

whether attribute is readable

**Type**

bool

**writable**

whether attribute is writable

**Type**

bool

**implemented**

whether the attribute is implemented in the given camera (normally always True)

**Type**

bool

**available**

whether the attribute can be changed or called

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**inc**

minimal attribute increment value (if applicable)

**Type**

float or int

**units**

attribute units (if applicable)

**repr**

shows what a numerical unit represents; can be "lin", "log", "bool", "pure", "hex", or "unknown"

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**update\_limits()**

Update minimal and maximal attribute limits and return tuple (min, max, inc)

**truncate\_value(value)**

Truncate value to lie within attribute limits

**get\_value(enum\_as\_str=True)**

Get attribute value.

If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_value(value, truncate=True)**

Set attribute value.

If `truncate==True`, automatically truncate value to lie within allowed range.

**call\_command()**

Execute the given command

**class** pylablib.devices.Basler.pylon.**TDeviceInfo**(*name, model, serial, devclass, devversion, vendor, friendly\_name, user\_name, props*)

Bases: `tuple`

**devclass****devversion****friendly\_name****model****name****props****serial****user\_name**

**vendor**

**class** pylablib.devices.Basler.pylon.BaslerPylonCamera(*idx=0, name=None*)

Bases: *IROIcamera*, *IAttributeCamera*, *IExposureCamera*

Generic Basler pylon camera interface.

**Parameters**

- **idx** – camera index among the cameras listed using *list\_cameras()*
- **name** – camera name; if specified, then *idx* is ignored and the camera is determined based on the provided name

**Error** = <Mock name='mock.BaslerError' id='140527670172560'>

**TimeoutError** = <Mock spec='str' id='140527670170256'>

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**post\_open()**

Additional setup after camera opening

**get\_attribute\_value**(*name, error\_on\_missing=True, default=None, enum\_as\_str=True*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not None, assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. If *enum\_as\_str==True*, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_attribute\_value**(*name, value, truncate=True, error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and *error\_on\_missing==True*, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If *truncate==True*, truncate value to lie within attribute range.

**call\_command**(*name*)

Execute the given command

**get\_all\_attribute\_values**(*root="", enum\_as\_str=True, ignore\_errors=True*)

Get values of all attributes with the given *root*

**set\_all\_attribute\_values**(*settings, root="", truncate=True*)

Set values of all attributes with the given *root*.

If *truncate==True*, truncate value to lie within attribute range.

**get\_device\_info()**

Get camera information.

Return tuple (name, model, serial, devclass, devversion, vendor, friendly\_name, user\_name, props).

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi(hstart=0, hend=None, vstart=0, vend=None)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_exposure()**

Get current exposure

**set\_exposure(exposure)**

Set camera exposure

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**set\_frame\_period(frame\_period)**

Set frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (*exposure*, *frame\_period*).

**class BufferManager(strm, size, nbuff)**

Bases: `object`

Buffer manager, which deals with buffer memory allocation, registering and deregistering, and retrieving the result and the leftovers

**register()**

Register buffers

**deregister()**

Deregister buffers

**get\_buffer(fid)**

Get buffer corresponding to the given frame index

**get\_handle(fid)**

Get buffer handle corresponding to the given frame index

**get\_all\_handles()**

Get all buffer handles as a ctypes array

**queue(*idx=None*)**

Queue a buffer with the given index or all buffers

**retrieve()**

Retrieve the next buffer and return its info and whether it is ready

**flush()**

Retrieve all leftover buffers

**class ScheduleLooper**

Bases: `object`

Cython-based schedule loop manager.

Runs the loop function and provides callback storage.

**start\_loop(*buff\_mgr*)**

Start loop serving the given buffer manager

**stop\_loop()**

Stop the loop thread

**is\_looping()**

Check if the loop is running

**get\_status()**

Get the current loop status, which is the tuple (acquired,)

**setup\_acquisition(*mode='sequence', nframes=100*)**

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frame buffers.

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as `:meth:`setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**enable\_raw\_readout(*enable='rows'*)**

Enable raw frame transfer.

Should be used if the camera uses unsupported pixel format. Can be "frame" (return the whole frame as a 1D "u1" numpy array), "rows" (return a 2D array, where each row corresponds to a single image row), or False (convert to image data, or raise an error if the format is not supported; default)



**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attributes(copy=False)**

Return a dictionary of all available attributes.

If *copy*==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by *get\_frame\_info\_fields()*; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

#### **get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

#### **get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

#### **get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

#### **get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

#### **get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

#### **grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

#### **is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

#### **pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*,

stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (None means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (None means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==`True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

## Module contents

### pylablib.devices.BitFlow package

#### Submodules

#### pylablib.devices.BitFlow.BitFlow module

**exception** pylablib.devices.BitFlow.BitFlow.**BitFlowError**

Bases: `DeviceError`

Generic BitFlow devices error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.BitFlow.BitFlow.BitFlowTimeoutError`

Bases: `BitFlowError`

BitFlow frame timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.devices.BitFlow.BitFlow.TDeviceInfo(idx, model, idreg)`

Bases: `tuple`

**idreg**

**idx**

**model**

`pylablib.devices.BitFlow.BitFlow.list_cameras()`

List all cameras available through BitFlow interface

`pylablib.devices.BitFlow.BitFlow.get_cameras_number()`

Get number of connected BitFlow cameras

**class** `pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber(bitflow_idx=0, bitflow_camfile=None, do_open=True, **kwargs)`

Bases: `IROICamera`

Generic BitFlow frame grabber interface.

Compared to `BitFlowCamera`, has more permissive initialization arguments, which simplifies its use as a base class for expanded cameras.

#### Parameters

- **bitflow\_idx** – board index, starting from 0
- **bitflow\_camfile** – if not `None`, a path to a valid camera file used for this frame grabber and camera combination; in this case, a temporary camera file is generated based on the provided one and used to change some otherwise unavailable camera parameters such as ROI and pixel bit depth (they are otherwise fixed to whatever is specified in the default camera file)
- **do\_open** – if `False`, skip the last step of opening the device (should be opened in a subclass)

#### Error

alias of `BitFlowError`

#### TimeoutError

alias of `BitFlowTimeoutError`

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get camera model data.

Return tuple (*idx*, *model*, *idreg*) with the board index, model number and the setting of the ID switch on the board

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi(*hstart=0, hend=None, vstart=0, vend=None*)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_grabber\_roi(*hstart=0, hend=None, vstart=0, vend=None*)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits(*hbin=1, vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_grabber\_roi\_limits(*hbin=1, vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**class BufferManager**(*cam*)

Bases: `object`

Buffer manager: stores, constantly reads and re-schedules buffers, keeps track of acquired frames and buffer overflow events

**reset()**

Reset counter (on frame acquisition)

**start\_loop()**

Start buffer scheduling loop

**stop\_loop()**

Stop buffer scheduling loop

**is\_running()**

Check if the buffer loop is running

**get\_status()**

Get counter status: tuple (acquired,)

**setup\_acquisition**(*mode='sequence', nframes=100, frame\_merge=1*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frames in the acquisition buffer. *frame\_merge* specifies the number of frames to merge together to form one buffer; if it is larger than 1, several camera frames will be merged into a single frame grabber "super-frame" for acquisition, to lower the effective frame rate (which is capped at 2-4kFPS due to the necessity of Python loops). This is done transparently for the user, so the only visible change is the fact that the number of acquired frames is always updated in quanta of *frame\_merge*.

**clear\_acquisition()**

Clear all acquisition details and free all buffers

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**FrameTransferError**

alias of `DefaultFrameTransferError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)



**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.BitFlow.BitFlow.BitFlowCamera`(*idx=0*, *camfile=None*)

Bases: `BitFlowFrameGrabber`

Generic BitFlow camera interface.

#### Parameters

**idx** – board index, starting from 0

**class** `BufferManager`(*cam*)

Bases: `object`

Buffer manager: stores, constantly reads and re-schedules buffers, keeps track of acquired frames and buffer overflow events

#### `get_status()`

Get counter status: tuple (acquired,)

#### `is_running()`

Check if the buffer loop is running

#### `reset()`

Reset counter (on frame acquisition)

#### `start_loop()`

Start buffer scheduling loop

#### `stop_loop()`

Stop buffer scheduling loop

#### **Error**

alias of `BitFlowError`

#### **FrameTransferError**

alias of `DefaultFrameTransferError`

#### **TimeoutError**

alias of `BitFlowTimeoutError`

#### `acquisition_in_progress()`

Check if acquisition is in progress

#### `apply_settings(settings)`

Apply the settings.

*settings* is the dict {**name**: **value**} of the device available settings. Non-applicable settings are ignored.

#### `clear_acquisition()`

Clear all acquisition details and free all buffers

#### `close()`

Close connection to the camera

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info()**

Get camera model data.

Return tuple (idx, model, idreg) with the board index, model number and the setting of the ID switch on the board

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**is\_opened**()

Check if the device is connected

**open**()

Open connection to the camera

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (*first* inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fnt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fnt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_grabber\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**setup\_acquisition**(*mode*='sequence', *nframes*=100, *frame\_merge*=1)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frames in the acquisition buffer. *frame\_merge* specifies the number of frames to merge together to form one buffer; if it is larger than 1, several camera frames will be merged into a single frame grabber "super-frame" for acquisition, to lower the effective frame rate (which is capped at 2-4kFPS due to the necessity of Python loops). This is done transparently for the user, so the only visible change is the fact that the number of acquired frames is always updated in quanta of *frame\_merge*.

**snap**(*timeout*=5.0, *return\_info*=False)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since*='lastread', *nframes*=1, *timeout*=20.0, *error\_on\_stopped*=False)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** pylablib.devices.BitFlow.BitFlow.CameraFileEditor

Bases: `object`

Camera file editor based on XML ElementTree parser.

Provides methods for loading and saving the tree, and to change basic parameters in the default operational mode.

**load**(*path*, *clean*=True)

Load file from the given path and optionally check the structure remove the non-default modes

**save**(*path*)

Save file to the given path

**clean\_modes**()

Check the loaded tree structure and remove non-default operational modes

**get\_mode\_parameters**()

Get default operational mode parameters.

Return tuple (*size*, *fmt*, *bpp*) with the acquisition size (*xsize*, *ysize*), format (e.g., "1X2-1Y") and the number of bits per pixel. If the tree is not loaded or mode is not present, return None.



**set\_mode\_parameters**(*size=None, fmt=None, bpp=None*)

Get default operational mode parameters.

*size* is the acquisition size (*xsize*, *ysize*), *fmt* is the tap format (e.g., "1X2-1Y"), and *bpp* is the number of bits per pixel. Parameters set to *None* stay unchanged. Return *True* if any parameters have changed their values and *False* otherwise.

## Module contents

### pylablib.devices.Conrad package

#### Submodules

#### pylablib.devices.Conrad.base module

**exception** pylablib.devices.Conrad.base.**ConradError**

Bases: *DeviceError*

Generic Conrad devices error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Conrad.base.**ConradBackendError**(*exc*)

Bases: *ConradError*, *DeviceBackendError*

Generic Conrad backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Conrad.base.**RelayBoard**(*conn, start\_addr=1*)

Bases: *ICommBackendWrapper*

Conrad relay board controller

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **start\_addr** – address which is assigned to the first board in the chain upon initialization; all following boards increase the address by 1

#### Error

alias of *ConradError*

**open()**

Open the connection to the board

**class TMessage**(*comm, addr, data*)

Bases: `tuple`

**addr**

**comm**

**data**

**query**(*comm, addr=1, data=0, multi\_result=False*)

Send a query with the given command, address and data.

If `multi_result==False`, read a single reply frame; otherwise, keep reading until reply with the same command as sent is received (used in initialization and broadcast queries).

**get\_all\_relays**(*addr=1*)

Get all relay states.

If *addr* is not 0, return dictionary `{relay:value}`, where `relay` is the relay index on the board (between 1 and 8 inclusive). If `addr==0` (broadcast), return dictionary `{addr:board_state}`, where `board_state` is in turn a state dictionary is described above.

**set\_all\_relays**(*values, addr=1*)

Set all relay states.

*values* can be a list (listing relay states from lowest to highest), or a dictionary `{relay:value}`, where relays are numbered from 1 to 8. Relays without values are kept unchanged. If `addr==0`, broadcast to all boards

**get\_relay**(*relay, addr=1*)

Get the state at a given relay (indexed from 1 to 8 inclusive)

**set\_relay**(*relay, enable=True, addr=1*)

Get the state at a given relay (indexed from 1 to 8 inclusive)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict `{name: value}` of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict `{name: value}` containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**Module contents****pylablib.devices.Cryocon package****Submodules****pylablib.devices.Cryocon.base module****exception** pylablib.devices.Cryocon.base.CryoconError

Bases: *DeviceError*

Generic Cryocon devices error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Cryocon.base.CryoconBackendError(*exc*)

Bases: *CryoconError*, *DeviceBackendError*

Generic Lakeshore backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Cryocon.base.Cryocon1x(conn, nchannels='auto')

Bases: [SCPIDevice](#)

Cryocon 1x series (12C, 14C, 18C) temperature controller.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of [CryoconError](#)

**ReraiseError**

alias of [CryoconBackendError](#)

**get\_number\_of\_channels()**

Return total number of channels in the device (2, 4, or 8)

**get\_display\_units(channel)**

**set\_display\_units(channel, units)**

**get\_temperature(channel, display\_units=False)**

Get a reading on a given channel.

If display\_units==True, return reading in the display units; otherwise, return reading in Kelvin. If in this case the display units are "S" (sensor), set them to Kelvin to get the reading. If sensor is disconnected, return None.

**get\_all\_temperatures(display\_units=False)**

Get readings on all channels.

If display\_units==True, return reading in the display units; otherwise, return reading in Kelvin. If in this case the display units are "S" (sensor), set them to Kelvin to get the reading. If sensor is disconnected, return None.

**get\_sensor\_reading(channel)**

Get readings (in sensor units) on a given channel (1 to 8)

**get\_all\_sensor\_readings()**

Get readings (in sensor units) on all channels

**get\_sensor\_kind(channel)**

Get sensor kind of a given channel (1 to 8)

**get\_all\_sensor\_kinds()**

Get readings (in sensor units) on all channels

**set\_sensor\_kind(channel, kind)**

Set sensor kind of a given channel (1 to 8).

Can be an integer using internal classification (see manual), or one of "none", "S900", "DT670", "DT470", "S950", "SI410", "Pt100", "Pt1k", "Pt10k", "ThFe", "R0105", "R0600". Setting kind to "none" disables the sensor.

**BackendError**

alias of *DeviceBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type*='sync', *timeout*=None, *wait\_callback*=None)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout*=None, *wait\_callback*=None)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg*=None, *arg\_type*=None, *unit*=None, *bool\_selector*=None, *wait\_sync*=None, *read\_echo*=False, *read\_echo\_delay*=0.0)

Send a command.

### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.Cryomagnetics package

#### Submodules

#### pylablib.devices.Cryomagnetics.base module

**exception** pylablib.devices.Cryomagnetics.base.**CryomagneticsError**

Bases: *DeviceError*

Generic Cryomagnetics devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Cryomagnetics.base.**CryomagneticsBackendError**(*exc*)

Bases: *CryomagneticsError*, *DeviceBackendError*

Generic Cryomagnetics backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Cryomagnetics.base.**LM500**(*conn*)

Bases: *SCPIDevice*

Cryomagnetics LM500/510 level monitor.

Channels are enumerated from 1. To abort filling or reset a timeout, call *SCPIDevice.reset()* method.

#### Parameters

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

#### Error

alias of *CryomagneticsError*

#### ReraiseError

alias of *CryomagneticsBackendError*

**close()**

Close connection to the device

**get\_channel()**

Get current measurement channel

**select\_channel**(*channel=1*)

Select the current measurement channel



**get\_type**(*channel=None*)

Get type of a given channel ("lhe" or "ln")

**get\_mode**(*channel=None*)

Get measurement mode at the given channel (None for the currently selected channel).

Can be either 'sample\_hold', or 'continuous'.

**set\_mode**(*mode, channel=None*)

Set measurement mode at the given channel (None for the current channel).

Can be either 'sample\_hold', or 'continuous'.

**get\_interval**(*channel=None*)

Get measurement interval (in seconds) in sample/hold mode at the given channel (None for the current channel)

**set\_interval**(*intvl, channel=None*)

Set measurement interval (in seconds) in sample/hold mode at the given channel (None for the current channel)

**start\_measurement**(*channel=None*)

Initialize measurement on a given channel

**wait\_for\_measurement**(*channel=None, timeout=None*)

Wait for the measurement on a given channel to finish

**get\_level**(*channel=None*)

Get level reading on a given channel

**measure\_level**(*channel=None*)

Measure the level (perform the measurement and return the result) on a given channel

**start\_fill**(*channel=None*)

Initialize filling at a given channel (None for the current channel)

**get\_fill\_status**(*channel=None*)

Get filling status at a given channels (None for the current channel).

Return either "off" (filling is off), "timeout" (filling timed out) or a float (time since filling started, in seconds).

**get\_low\_level**(*channel=None*)

Get low level (automated refill start) setting on a given channel (None for the current channel)

**set\_low\_level**(*level, channel=None*)

Set low level (automated refill start) setting on a given channel (None for the current channel)

**get\_high\_level**(*channel=None*)

Get high level (automated refill stop) setting on a given channel (None for the current channel)

**set\_high\_level**(*level, channel=None*)

Set high level (automated refill stop) setting on a given channel (None for the current channel)

**BackendError**

alias of [DeviceBackendError](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout*=None)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include*=0)

Get dict {**name**: **value**} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status**(*include*=0)

Get dict {**name**: **value**} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id**(*timeout*=None)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include*=0)

Get dict {**name**: **value**} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened**()

Check if the device is connected

**lock**(*timeout*=None)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout*=None)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform [wait\\_sync\(\)](#)), 'dev' (perform [wait\\_dev\(\)](#)) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., *arg\_type*='{0};{1}' with *arg*=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (false\_value, true\_value) of two strings to represent bool argument; by default, use *.\_bool\_selector* attribute.
- **wait\_sync** – if True, append the sync command (specified as *.\_wait\_sync\_comm* attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default *.\_default\_write\_sync* attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if *read\_echo*==True.

**class** pylablib.devices.Cryomagnetics.base.LM510(*conn*)

Bases: *LM500*

Cryomagnetics 510 level monitor.

Compared to *LM500*, adds additional specific methods to enable/disable automatic refill.

Channels are enumerated from 1. To abort filling or reset a timeout, call *SCPIDevice.reset()* method.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**set\_control\_mode**(*mode, channel=None*)

Set automated refill mode on a given channel (None for the current channel); can be "off" or "auto"

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *CryomagneticsError*

**ReraiseError**

alias of *CryomagneticsBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close connection to the device

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_channel()**

Get current measurement channel

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_fill\_status(channel=None)**

Get filling status at a given channels (None for the current channel).

Return either "off" (filling is off), "timeout" (filling timed out) or a float (time since filling started, in seconds).

**get\_full\_info(include=0)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_high\_level(channel=None)**

Get high level (automated refill stop) setting on a given channel (None for the current channel)

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_interval**(*channel=None*)

Get measurement interval (in seconds) in sample/hold mode at the given channel (*None* for the current channel)

**get\_level**(*channel=None*)

Get level reading on a given channel

**get\_low\_level**(*channel=None*)

Get low level (automated refill start) setting on a given channel (*None* for the current channel)

**get\_mode**(*channel=None*)

Get measurement mode at the given channel (*None* for the currently selected channel).

Can be either 'sample\_hold', or 'continuous'.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_type**(*channel=None*)

Get type of a given channel ("lhc" or "ln")

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**measure\_level**(*channel=None*)

Measure the level (perform the measurement and return the result) on a given channel

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**select\_channel**(*channel=1*)

Select the current measurement channel

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_high\_level**(*level, channel=None*)

Set high level (automated refill stop) setting on a given channel (None for the current channel)

**set\_interval**(*intvl, channel=None*)

Set measurement interval (in seconds) in sample/hold mode at the given channel (None for the current channel)

**set\_low\_level**(*level, channel=None*)

Set low level (automated refill start) setting on a given channel (None for the current channel)

**set\_mode**(*mode, channel=None*)

Set measurement mode at the given channel (None for the current channel).

Can be either 'sample\_hold', or 'continuous'.

**sleep**(*delay*)

Wait for *delay* seconds

**start\_fill**(*channel=None*)

Initialize filling at a given channel (None for the current channel)

**start\_measurement**(*channel=None*)

Initialize measurement on a given channel

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive *write()* operations are bundled together with ; delimiter. The actual write is performed at the *read()/ask()* operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_for\_measurement**(*channel=None, timeout=None*)

Wait for the measurement on a given channel to finish

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{: .3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.



## Module contents

### pylablib.devices.DCAM package

#### Submodules

### pylablib.devices.DCAM.DCAM module

**class** pylablib.devices.DCAM.DCAM.**LibraryController**(*lib*)

Bases: *LibraryController*

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

pylablib.devices.DCAM.DCAM.**restart\_lib**()

pylablib.devices.DCAM.DCAM.**get\_cameras\_number**()

Get number of connected DCAM cameras

**class** pylablib.devices.DCAM.DCAM.**DCAMAttribute**(*handle*, *pid*)

Bases: *object*

DCAM camera attribute.

Allows to query and set values and get additional information. Usually created automatically by a DCAM camera instance, but could also be created manually.

#### Parameters

- **handle** – DCAM camera handle
- **pid** – attribute id

**name**

attribute name

**kind**

attribute kind; can be "int", "float", "enum", or "none" (can't determine)

**Type**

str

**readable**

whether attribute is readable

**Type**

bool

**writable**

whether attribute is writable

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float

**max**

maximal attribute value (if applicable)

**Type**

float

**step**

attribute value step (if applicable)

**Type**

float

**unit**

attribute units (index value)

**Type**

int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**as\_text** (*value=None*)

Get the given attribute value as text (by default, current value)

**update\_limits()**

Update minimal and maximal attribute limits and return tuple (min, max)

**get\_value**(*enum\_as\_str=False*)

Get current attribute value.

If *enum\_as\_str*==True, try to represent enums as their string values; otherwise, return their integer values (only integers can be used for setting).

**set\_value**(*value*)

Set attribute value

**class** pylablib.devices.DCAM.DCAM.**TDeviceInfo**(*vendor, model, serial\_number, camera\_version*)

Bases: `tuple`

**camera\_version**

**model**

**serial\_number**

**vendor**

**class** pylablib.devices.DCAM.DCAM.**TFrameInfo**(*frame\_index, framestamp, timestamp\_us, camerastamp, position, pixeltype*)

Bases: `tuple`

**camerastamp**

**frame\_index**

**framestamp**

**pixeltype**

**position**

**timestamp\_us**

**class** pylablib.devices.DCAM.DCAM.**DCAMCamera**(*idx=0*)

Bases: `IBinROICamera`, `IExposureCamera`, `IAttributeCamera`

**Error** = <Mock name='mock.DCAMError' id='140527652328336'>

**TimeoutError** = <Mock spec='str' id='140527657828688'>

**open**()

Open connection to the camera

**close**()

Close connection to the camera

**is\_opened**()

Check if the device is connected

**get\_device\_info**()

Get camera model data.

Return tuple (vendor, model, serial\_number, camera\_version).

**get\_attribute\_value**(*name*, *enum\_as\_str=False*, *error\_on\_missing=True*, *default=None*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not *None*, assume that *error\_on\_missing==False*. If *enum\_as\_str==True*, try to represent enums as their string values; otherwise, return their integer values (only integers can be used for setting).

**set\_attribute\_value**(*name*, *value*, *error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and *error\_on\_missing==True*, raise error; otherwise, do nothing.

**get\_all\_attribute\_values**(*root=""*, *enum\_as\_str=False*)

Get values of all attributes.

If *enum\_as\_str==True*, try to represent enums as their string values; otherwise, return their integer values (only integers can be used for setting).

**set\_all\_attribute\_values**(*settings*)

Set values of all attribute in the given dictionary

**set\_trigger\_mode**(*mode*)

Set trigger mode.

Can be "int" (internal), "ext" (external), or "software" (software trigger).

**get\_trigger\_mode**()

Get trigger mode.

Can be "int" (internal), "ext" (external), or "software" (software trigger).

**get\_all\_trigger\_modes**()

Return the list of all available trigger modes

**setup\_ext\_trigger**(*invert=False*, *delay=0.0*)

Setup external trigger (inversion and delay)

**get\_ext\_trigger\_parameters**()

Return external trigger parameters (inversion and delay)

**send\_software\_trigger**()

Send software trigger signal

**set\_exposure**(*exposure*)

Set camera exposure

**get\_exposure**()

Set current exposure

**set\_readout\_speed**(*speed='fast'*)

Set readout speed (can be "fast" or "slow")

**get\_readout\_speed**()

Set current readout speed

**get\_all\_readout\_speeds**()

Return the list of all available readout speeds

**get\_frame\_readout\_time()**

Set current frame readout time

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (exposure, frame\_period).

**get\_defect\_correct\_mode()**

Check if the defect pixel correction mode is on

**set\_defect\_correct\_mode(enabled=True)**

Enable or disable the defect pixel correction mode

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend, hbin, vbin).

**set\_roi(hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1)**

Set current ROI.

By default, all non-supplied parameters take extreme values. Binning is the same for both axes, so value of *vbin* is ignored (it is left for compatibility).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**setup\_acquisition(mode='sequence', nframes=100)**

Setup acquisition.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* determines number of frames to acquire in the single mode, or size of the ring buffer in the "sequence" mode (by default, 100).

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as *meth: `setup\_acquisition`*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**get\_status()**

Get acquisition status.

Can be "busy" (capturing in progress), "ready" (ready for capturing), "stable" (not prepared for capturing), "unstable" (can't be prepared for capturing), or "error" (some other error).

**acquisition\_in\_progress()**

Check if acquisition is in progress

**get\_transfer\_info()**

Get frame transfer info.

Return tuple (last\_buff, frame\_count), where last\_buff is the index of the last filled buffer, and frame\_count is the total number of acquired frames.

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attributes(copy=False)**

Return a dictionary of all available attributes.

If copy==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by *get\_frame\_info\_fields()*; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (`first`, `last`) with images range (first inclusive). If no images are available, return `None`. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {`name`: `value`} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if `None`, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If `return_info==True`,

return tuple (frames, infos), where infos is a list of frame info tuples (camera-dependent); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is None.

#### **is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

#### **pausing\_acquisition**(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (None means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (None means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

#### **read\_newest\_image**(peek=False, return\_info=False)

Read the newest un-read image.

If no un-read frames are available, return None. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

#### **read\_oldest\_image**(peek=False, return\_info=False)

Read the oldest un-read image.

If no un-read frames are available, return None. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

#### **set\_device\_variable**(key, value)

Set the value of a settings parameter

#### **set\_frame\_format**(fmt)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

#### **set\_frame\_info\_format**(fmt, include\_fields=None)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)



If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==`True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If *peek*==`True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==`True`, return tuple (*frames*, *infos*), where *infos* is a list of `TFrameInfo` instances describing frame index, framestamp and timestamp, camera stamp, frame location on the sensor, and pixel type; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is `None`. if *return\_rng*==`True`, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

## Module contents

### pylablib.devices.ElektroAutomatik package

#### Submodules

### pylablib.devices.ElektroAutomatik.base module

**exception** pylablib.devices.ElektroAutomatik.base.**ElektroAutomatikError**

Bases: *DeviceError*

Generic Elektro Automatik device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.ElektroAutomatik.base.**ElektroAutomatikBackendError**(*exc*)

Bases: *ElektroAutomatikError*, *DeviceBackendError*

Generic Elektro Automatik backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.ElektroAutomatik.base.**TDeviceInfo**(*model, manufacturer, serial\_no, article\_no, sw\_ver*)

Bases: *tuple*

**article\_no**

**manufacturer**

**model**

**serial\_no**

**sw\_ver**

**class** pylablib.devices.ElektroAutomatik.base.**TOutputLimits**(*voltage, current, power*)

Bases: *tuple*

**current**

**power**

**voltage**

**class** pylablib.devices.ElektroAutomatik.base.**TStatus**(*enabled, mode, ovp, ocp, opp, otp*)

Bases: *tuple*

**enabled**

**mode**

**ocp**

**opp**

**otp**

**ovp**

**class** `pylablib.devices.ElektroAutomatik.base.PS2000B(conn, remote_mode='force')`

Bases: `ICommBackendWrapper`

Elektro Automatik PS2000B series power supply.

#### Parameters

- **conn** – serial connection parameters (usually, COM-port address)
- **remote\_mode** – approach to setting the remote mode; can be "force" (enable on connection, disable on disconnection) or "manual" (do nothing about it, should be enabled or disabled automatically). In the remote mode the device is controlled from the PC (front panel controls are disabled), while in the local mode it can only be queried remotely, but not changed.

#### Error

alias of `ElektroAutomatikError`

**class** `TTelegram(obj, data, dnode)`

Bases: `tuple`

**data**

**dnode**

**obj**

**open()**

Open the backend

**close()**

Close the backend

**query(obj, dlen, dnode=0, kind='raw')**

Query value of the given object.

*dlen* specifies the value length and *dnode* sets the device node (only relevant for multi-source models). *kind* specifies the result kind; can be "raw" (raw bytes), "str" (string), "int" (2-byte integer) or "float" (r-byte float).

**comm(obj, value, dnode=0, kind='int')**

Set value of the given object.

*dnode* sets the device node (only relevant for multi-source models). *kind* specifies the value kind; can be "raw" (raw bytes), or "int" (2-byte integer).

**get\_device\_info()**

Get device information.

Return tuple (model, manufacturer, serial\_no, article\_no, sw\_ver).

**get\_output\_limits()**

Get nominal output limits.

Return tuple (voltage, current, power).

**is\_remote\_enabled()**

Check if the remote-control mode is enabled (if it is disabled, output and limit values can be read but not set)

**enable\_remote(enable=True)**

Enable or disable the remote-control mode (if it is disabled, output and limit values can be read but not set)

**is\_output\_enabled()**

Check if the output is enabled

**enable\_output(enable=True)**

Enable or disable the output

**get\_status()**

Get device status.

Return tuple (mode, ovp, ocp, opp, otp), where mode is the output mode ("cv" or "cc") and the rest of the values show if the corresponding protection is tripped.

**get\_voltage\_setpoint()**

Get output voltage setpoint

**get\_voltage()**

Get the actual output voltage

**set\_voltage(value)**

Set output voltage setpoint

**get\_current\_setpoint()**

Get output current setpoint

**get\_current()**

Get the actual output current

**set\_current(value)**

Set output current setpoint

**get\_ovp\_threshold()**

Get over-voltage protection threshold

**set\_ovp\_threshold(value)**

Set over-voltage protection threshold

**get\_ocp\_threshold()**

Get over-current protection threshold

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_ocp\_threshold**(*value*)

Set over-current protection threshold

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**Module contents****pylablib.devices.HighFinesse package****Submodules****pylablib.devices.HighFinesse.wlm module**

`pylablib.devices.HighFinesse.wlm.muxchannel(*args, **kwargs)`

Multiplex the function over its channel argument

**class** `pylablib.devices.HighFinesse.wlm.TDeviceInfo(model, serial_number, revision_number, compilation_number)`

Bases: `tuple`

`compilation_number`

**model**

**revision\_number**

**serial\_number**

```
class pylablib.devices.HighFinesse.wlm.WLM(version=None, dll_path=None, app_path=None,
                                             autostart=True)
```

Bases: *IDevice*

Generic HighFinesse wavemeter.

#### Parameters

- **version** (*int*) – wavemeter version; if *None*, use any available version
- **dll\_path** – path to wlmData.dll; if *None*, use standard locations or search based on the version
- **app\_path** – path to the wavemeter server application (looks like wlm\_ws.exe or wlm\_ws7.exe); if *None*, try to autodetect, or rely on the server already running
- **autostart** – if *True*, start measurements automatically (if the wavemeter server app is not running, it will launch with the measurements stopped).

**Error** = <Mock name='mock.HighFinesseError' id='140527647698704'>

**open()**

Open the connection to the wavemeter

**close()**

Close the connection to the wavemeter

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get the wavemeter info.

Return tuple (model, serial\_number, revision\_number, compilation\_number).

**start\_measurement()**

Start wavemeter measurement

**stop\_measurement()**

Stop wavemeter measurement

**is\_measurement\_running()**

Check if the measurement is running

**set\_read\_mode(mode)**

Set value read mode, which applies to *get\_frequency()* and *get\_wavelength()*.

Can be "latest" (always return the latest measurement result; default), or "single" (if there's no new measurement since the last call, the result is "noval" which, depending on the arguments, causes wait, is returned as is, or raises an error).

**get\_read\_mode()**

Get value read mode, which applies to [`get\_frequency\(\)`](#) and [`get\_wavelength\(\)`](#).

Can be "latest" (always return the latest measurement result; default), or "single" (if there's no new measurement since the last call, the result is "noval" which, depending on the arguments, causes wait, is returned as is, or raises an error).

**get\_channels\_number(*refresh=True*)**

Get number of channels in the wavemeter

**get\_default\_channel()**

Get the default channel (starting from 1) which is used for querying

**set\_default\_channel(*channel*)**

Set the default channel (starting from 1) which is used for querying

**get\_frequency(*channel=None, error\_on\_invalid=True, wait=True, timeout=5.0*)**

Get the wavemeter readings (in Hz) on a given channel.

*channel* is the measurement channel (starting from 1); if *None*, use the default channel. If *error\_on\_invalid==True*, raise an error if the measurement is invalid (e.g., over- or underexposure); otherwise, the method can return "under" if the meter is underexposed or "over" if it is overexposed, "badsig" if there is no calculable signal, "noval" if there are no values acquired yet, "nosig" if there is no signal, or "nowlm" if there is no connection to the wavemeter. If *wait==True* and the result is "noval" (e.g., if the read mode is "single" and no new value has been acquired since the last call), wait for at most *timeout* until a new value appears; if the *timeout* has passed, use the default behavior (error or "noval" result).

**get\_wavelength(*channel=None, error\_on\_invalid=True, wait=True, timeout=5.0*)**

Get the wavemeter readings (in m, and in vacuum).

*channel* is the measurement channel (starting from 1); if *None*, use the default channel. If *error\_on\_invalid==True*, raise an error if the measurement is invalid (e.g., over- or underexposure); otherwise, the method can return "under" if the meter is underexposed or "over" if it is overexposed, "badsig" if there is no calculable signal, "noval" if there are no values acquired yet, "nosig" if there is no signal, or "nowlm" if there is no connection to the wavemeter. If *wait==True* and the result is "noval" (e.g., if the read mode is "single" and no new value has been acquired since the last call), wait for at most *timeout* until a new value appears; if the *timeout* has passed, use the default behavior (error or "noval" result).

**get\_exposure\_mode(*channel=None*)**

Get the exposure mode ("manual" or "auto") at the given channel

**set\_exposure\_mode(*mode='auto', channel=None*)**

Set the exposure mode ("manual" or "auto") at the given channel

**get\_exposure(*sensor=1, channel=None*)**

Get the exposure for a given channel and sensor (starting from 1)

**set\_exposure(*exposure, sensor=1, channel=None*)**

Manually set the exposure for a given channel and sensor (starting from 1)

**get\_switcher\_mode()**

Get the switcher mode ("off" for manual switching or "on" for cycling mode)

**set\_switcher\_mode(*mode='on'*)**

Set the switcher mode ("off" for manual switching or "on" for cycling mode)

**get\_active\_channel()**

Get the current active channel

**set\_active\_channel(channel, automode=True)**

Set the current switcher channel.

Only makes sense in the manual ("off") switcher mode. If `automode==True`, switch to this mode automatically.

**is\_switcher\_channel\_enabled(channel, automode=True)**

Check whether the switcher channel enabled.

Only works in the cycling ("on") switcher mode. If `automode==True`, switch to this mode automatically.

**is\_switcher\_channel\_shown(channel, automode=True)**

Check whether the switcher channel is shown in the wavemeter control application.

Only works in the cycling ("on") switcher mode. If `automode==True`, switch to this mode automatically.

**enable\_switcher\_channel(channel, enable=True, show=None, automode=True)**

Enable or disable the current switcher channel in the switch mode.

Only works in the cycling ("on") switcher mode. If `automode==True`, switch to this mode automatically.

**get\_pulse\_mode()**

Get the current pulse mode.

Can be "cw" (CW laser mode), "int" (standard single-laser internally triggered mode), "ext" (single- or double-laser mode with external TTL trigger), or "opt" (double-laser mode with optical triggering).

**set\_pulse\_mode(mode)**

Set the current pulse mode.

Can be "cw" (CW laser mode), "int" (standard single-laser internally triggered mode), "ext" (single- or double-laser mode with external TTL trigger), or "opt" (double-laser mode with optical triggering).

**get\_precision\_mode()**

Set the current precision mode ("fine", "wide", or "grating")

**set\_precision\_mode(mode)**

Set the current precision mode ("fine", "wide", or "grating")

**get\_measurement\_interval()**

Set measurement interval (per channel), or None if the interval mode is off

**set\_measurement\_interval(interval=None)**

Set measurement interval (per channel).

None means that the interval mode is off.

**calibrate(source\_type, source\_frequency, channel=None)**

Initialize the calibration.

`source_type` is the calibration source type, which can be "hene\_633" (HeNe 633nm laser), "hene\_1152" (HeNe 1152nm laser), "hene\_free" (free-running HeNe laser), "nel" (Ne lamp), or "other" (other source). `source_frequency` is the exact source frequency (in Hz) sent through the given `channel`.



**get\_autocalibration\_parameters()**

Get up the automatic calibration parameters.

Return tuple (*enable*, *unit*, *period*), where *enable* determines if it is enabled, and *unit* and *period* together specify the calibration period. *unit* can be "start" (once on the measurement start; *period* is irrelevant here), "meas" (once every *period* frequency measurements), "min" (once every *period* minutes), "hours", or "days".

**setup\_autocalibration(enable=True, unit=None, period=None)**

Set up the automatic calibration parameters.

*enable* determines if it is enabled. *unit* and *period* together specify the calibration period. *unit* can be "start" (once on the measurement start; *period* is irrelevant here), "meas" (once every *period* frequency measurements), "min" (once every *period* minutes), "hours", or "days". Any None parameters are kept at the present value.

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**Module contents****pylablib.devices.Hubner package****Submodules****pylablib.devices.Hubner.Cobolt module**

```
class pylablib.devices.Hubner.Cobolt.TDeviceInfo(serial, model, name, firmware_version,  
                                                firmware_date, firmware_build_date)
```

Bases: [tuple](#)

**firmware\_build\_date**

**firmware\_date**

**firmware\_version**

**model**

**name**

**serial**

```
class pylablib.devices.Hubner.Cobolt.Cobolt(conn)
```

Bases: [ICommBackendWrapper](#)

Hubner Cobolt MLD/DPL lasers.

**Parameters**

**conn** – serial connection parameters (usually port)

**Error**

alias of [HubnerError](#)

```
query(comm, data_type='string', **kwargs)
```

Send a query to the device and parse the reply

```
get_device_info()
```

Get device information (serial number)

```
get_work_hours()
```

Return device operation hours

```
get_baseplate_temperature()
```

Return device base plate temperature (in C)

```
get_head_temperature()
```

Return device head (TEC) temperature (in C)

```
abort_autostart()
```

Abort autostart sequence

```
restart_autostart()
```

Restart autostart sequence

```
is_autostart_enabled()
```

Return whether the autostart sequence is enabled

```
get_error_state()
```

Return the current error (fault) state

```
clear_error()
```

Clear the error state

```
get_operating_mode()
```

Return the operating mode

**enable**(*enabled=True, autostart='auto'*)

Enable or disable the output.

*autostart* determines whether the autostart-enabled command is used or not (if "auto", try both and ignore the errors). Note that if *enabled==True*, this command does not usually turn on the laser, and requires the key switch to be turned off and back on.

**is\_enabled**()

Check if the output is on

**get\_key\_switch**()

Get the key switch state (True is on, False is off)

**get\_interlock**()

Get the interlock state (True is closed, False is open/fault)

**set\_output\_mode**(*mode*)

Set output mode ("ccurrent" for constant current, "cpower" for constant power, "mod" for modulation)

**get\_output\_mode**()

Get output mode ("ccurrent" for constant current, "cpower" for constant power, "mod" for modulation)

Can also return None if the mode can not be queried.

**get\_output\_power\_setpoint**()

Get output power setpoint (in W) in the constant power mode

**set\_output\_power**(*setpoint, set\_mode=True*)

Set output power setpoint (in W).

If *set\_mode==True*, switch the device to the constant power mode.

**get\_max\_output\_power**()

Get the maximal output power

**get\_output\_current\_setpoint**()

Get output current setpoint (in A) in the constant current mode

**set\_output\_current**(*setpoint, set\_mode=True*)

Set output current setpoint (in A).

If *set\_mode==True*, switch the device to the constant current mode.

**get\_max\_output\_current**()

Get the maximal output current

**get\_output\_power**()

Get actual current output power (in W)

**get\_output\_current**()

Get actual current drive current (in A)

**is\_analog\_modulation\_enabled**()

Check if the analog modulation is enabled

**enable\_analog\_modulation**(*enabled=True*)

Enable or disable the analog modulations

**is\_digital\_modulation\_enabled**()

Check if the digital modulation is enabled

**enable\_digital\_modulation**(*enabled=True*)

Enable or disable the digital modulations

**get\_modulation\_power\_setpoint**()

Get power setpoint (in W) in the modulation mode

**set\_modulation\_power**(*setpoint*)

Set power setpoint (in W) in the modulation mode

**get\_analog\_modulation\_impedance**()

Get analog modulation input impedance ("50ohm" or "highZ")

**set\_analog\_modulation\_impedance**(*impedance*)

Set analog modulation input impedance ("50ohm" or "highZ")

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## pylablib.devices.Hubner.base module

**exception** pylablib.devices.Hubner.base.**HubnerError**

Bases: [\*DeviceError\*](#)

Generic Hubner Photonics devices error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Hubner.base.**HubnerBackendError**(*exc*)

Bases: [\*HubnerError\*](#), [\*DeviceBackendError\*](#)

Generic Hubner Photonics backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## Module contents

### pylablib.devices.IMAQ package

#### Submodules

#### pylablib.devices.IMAQ.IMAQ module

pylablib.devices.IMAQ.IMAQ.**list\_cameras**()

List all cameras available through IMAQ interface

pylablib.devices.IMAQ.IMAQ.**get\_cameras\_number**()

Get number of connected IMAQ cameras

**class** pylablib.devices.IMAQ.IMAQ.**TDeviceInfo**(*serial\_number*, *interface*)

Bases: [\*tuple\*](#)

**interface**

**serial\_number**

```
class pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber(imaq_name='img0', do_open=True, **kwargs)
```

Bases: [IROICamera](#)

Generic IMAQ frame grabber interface.

Compared to [IMAQCamera](#), has more permissive initialization arguments, which simplifies its use as a base class for expanded cameras.

#### Parameters

- **imaq\_name** – interface name (can be learned by [list\\_cameras\(\)](#); usually, but not always, starts with "cam" or "img")
- **do\_open** – if False, skip the last step of opening the device (should be opened in a subclass)

```
Error = <Mock name='mock.IMAQError' id='140527719709904'>
```

```
TimeoutError = <Mock spec='str' id='140527693277200'>
```

```
open()
```

Open connection to the camera

```
close()
```

Close connection to the camera

```
reset()
```

Reset connection to the camera

```
is_opened()
```

Check if the device is connected

```
get_grabber_attribute_value(attr, default=None, kind='auto')
```

Get value of an attribute with a given name or index.

If *default* is not None, return *default* if the attribute is not supported; otherwise, raise an error. *kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

```
set_grabber_attribute_value(attr, value, kind='int32')
```

Set value of an attribute with a given name or index.

*kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

```
get_all_grabber_attribute_values()
```

Get a dictionary of all readable attributes.

The attributes types are autodetected, and some of the types of uncommon attributes may be misrepresented.

```
get_device_info()
```

Get camera model data.

Return tuple (serial, interface) with the board serial number and an the interface type (e.g., "1430" for NI PCIe-1430)

```
get_detector_size()
```

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi(hstart=0, hend=None, vstart=0, vend=None)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_grabber\_roi(hstart=0, hend=None, vstart=0, vend=None)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_grabber\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**configure\_trigger\_in(trig\_type, trig\_line=0, trig\_pol='high', trig\_action='none', timeout=None, reset\_acquisition=True)**

Configure input trigger.

**Parameters**

- **trig\_type** (*str*) – trigger source type; can be "ext", "rtsi", "iso\_in", or "software"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_action** (*str*) – trigger action; can be "none" (disable trigger), "capture" (start capturing), "stop" (stop capturing), "buffer" (capture a single frame), or "bufflist" (capture the whole buffer list once)

- **timeout** (*float*) – timeout in seconds; None means not timeout.
- **reset\_acquisition** (*bool*) – if the input triggers configuration has been changed, acquisition needs to be restart; if True, perform it automatically

**send\_software\_trigger()**

Send software trigger signal

**configure\_trigger\_out**(*trig\_type*, *trig\_line*=0, *trig\_pol*='high', *trig\_drive*='disable')

Configure trigger output.

#### Parameters

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_drive** (*str*) – trigger output signal; can be "disable" (disable drive), "acq\_in\_progress" (asserted when acquisition is started), "acq\_done" (asserted when acquisition is done), "unasserted" (force unasserted level), "asserted" (force asserted level), "hsync" (asserted on start of a single line start), "vsync" (asserted on start of a frame scan), "frame\_start" (asserted when a single frame is captured), or "frame\_done" (asserted when a single frame is done)

**read\_trigger**(*trig\_type*, *trig\_line*=0, *trig\_pol*='high')

Read current value of a trigger (input or output).

#### Parameters

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", "iso\_in", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"

**clear\_all\_triggers**(*reset\_acquisition*=True)

Disable all triggers of the session

If the input triggers configuration has been changed, acquisition needs to be restart; if *reset\_acquisition*==True, perform it automatically.

**setup\_serial\_params**(*write\_term*="", *datatype*='bytes')

Setup default serial communication parameters.

#### Parameters

- **write\_term** – default terminator character to be added to the sent messages
- **datatype** – type of the result of read commands; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string)

**get\_serial\_params()**

Return serial parameters as a tuple (*write\_term*, *datatype*)

**serial\_write**(*msg*, *timeout*=3.0, *term*=None)

Write message into CameraLink serial port.

#### Parameters

- **timeout** – operation timeout (in seconds)



- **term** – additional write terminator character to add to the message; if `None`, use the value set up using `setup_serial_params()` (by default, no additional terminator)

**serial\_read**(*n*, *timeout*=3.0, *datatype*=None)

Read specified number of bytes from CameraLink serial port.

#### Parameters

- **n** – number of bytes to read
- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if `None`, use the value set up using `setup_serial_params()` (by default, "bytes")

**serial\_readline**(*timeout*=3.0, *datatype*=None, *maxn*=1024)

Read bytes from CameraLink serial port until the termination character (defined in camera file) is encountered.

#### Parameters

- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if `None`, use the value set up using `setup_serial_params()` (by default, "bytes")
- **maxn** – maximal number of bytes to read

**serial\_flush**()

Flush CameraLink serial port

**setup\_acquisition**(*mode*='sequence', *nframes*=100)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that `IMAQCamera.acquisition_in_progress()` would still return `True` in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**clear\_acquisition**()

Clear all acquisition details and free all buffers

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as `:meth: ``setup_acquisition```. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is `None`). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**acquisition\_in\_progress**()

Check if acquisition is in progress

**FrameTransferError**

alias of `DefaultFrameTransferError`

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.IMAQ.IMAQ.IMAQCamera`(*name='img0'*)

Bases: [`IMAQFrameGrabber`](#)

Generic IMAQ camera interface.

**Parameters**

**name** – interface name (can be learned by `list_cameras()`; usually, but not always, starts with "cam" or "img")

**Error** = <Mock name='mock.IMAQError' id='140527719709904'>

**FrameTransferError**

alias of [`DefaultFrameTransferError`](#)

**TimeoutError** = <Mock spec='str' id='140527693277200'>

**acquisition\_in\_progress**()

Check if acquisition is in progress

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition**()

Clear all acquisition details and free all buffers

**clear\_all\_triggers**(*reset\_acquisition=True*)

Disable all triggers of the session

If the input triggers configuration has been changed, acquisition needs to be restart; if *reset\_acquisition*==True, perform it automatically.

**close**()

Close connection to the camera

**configure\_trigger\_in**(*trig\_type, trig\_line=0, trig\_pol='high', trig\_action='none', timeout=None, reset\_acquisition=True*)

Configure input trigger.

**Parameters**

- **trig\_type** (*str*) – trigger source type; can be "ext", "rtsi", "iso\_in", or "software"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_action** (*str*) – trigger action; can be "none" (disable trigger), "capture" (start capturing), "stop" (stop capturing), "buffer" (capture a single frame), or "bufflist" (capture the whole buffer list once)
- **timeout** (*float*) – timeout in seconds; None means not timeout.
- **reset\_acquisition** (*bool*) – if the input triggers configuration has been changed, acquisition needs to be restart; if True, perform it automatically

**configure\_trigger\_out**(*trig\_type*, *trig\_line*=0, *trig\_pol*='high', *trig\_drive*='disable')

Configure trigger output.

**Parameters**

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_drive** (*str*) – trigger output signal; can be "disable" (disable drive), "acq\_in\_progress" (asserted when acquisition is started), "acq\_done" (asserted when acquisition is done), "unasserted" (force unasserted level), "asserted" (force asserted level), "hsync" (asserted on start of a single line start), "vsync" (asserted on start of a frame scan), "frame\_start" (asserted when a single frame is captured), or "frame\_done" (asserted when a single frame is done)

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_grabber\_attribute\_values()**

Get a dictionary of all readable attributes.

The attributes types are autodetected, and some of the types of uncommon attributes may be misrepresented.

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info()**

Get camera model data.

Return tuple (serial, interface) with the board serial number and an the interface type (e.g., "1430" for NI PCIe-1430)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_grabber\_attribute\_value(attr, default=None, kind='auto')**

Get value of an attribute with a given name or index.

If *default* is not `None`, return *default* if the attribute is not supported; otherwise, raise an error. *kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_serial\_params()**

Return serial parameters as a tuple (*write\_term*, *datatype*)

**get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(*nframes=1*, *frame\_timeout=5.0*, *missing\_frame='skip'*, *return\_info=False*, *buff\_size=None*)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.



**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**open()**

Open connection to the camera

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress, acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first, last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames, infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame, info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame, info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_trigger**(*trig\_type, trig\_line=0, trig\_pol='high'*)

Read current value of a trigger (input or output).

**Parameters**

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", "iso\_in", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"

**reset()**

Reset connection to the camera

**send\_software\_trigger()**

Send software trigger signal

**serial\_flush()**

Flush CameraLink serial port

**serial\_read**(*n*, *timeout=3.0*, *datatype=None*)

Read specified number of bytes from CameraLink serial port.

**Parameters**

- **n** – number of bytes to read
- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")

**serial\_readline**(*timeout=3.0*, *datatype=None*, *maxn=1024*)

Read bytes from CameraLink serial port until the termination character (defined in camera file) is encountered.

**Parameters**

- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")
- **maxn** – maximal number of bytes to read

**serial\_write**(*msg*, *timeout=3.0*, *term=None*)

Write message into CameraLink serial port.

**Parameters**

- **timeout** – operation timeout (in seconds)
- **term** – additional write terminator character to add to the message; if *None*, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, no additional terminator)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D “chunk” arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the

frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fnt*, *include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_grabber\_attribute\_value**(*attr*, *value*, *kind='int32'*)

Set value of an attribute with a given name or index.

*kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**set\_grabber\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**setup\_acquisition**(*mode='sequence'*, *nframes=100*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that [IMAQCamera.acquisition\\_in\\_progress\(\)](#) would still return *True* in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**setup\_serial\_params**(*write\_term=""*, *datatype='bytes'*)

Setup default serial communication parameters.

### Parameters

- **write\_term** – default terminator character to be added to the sent messages
- **datatype** – type of the result of read commands; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped==True* and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

## pylablib.devices.IMAQ.niimaq\_attrtypes module

### Module contents

## pylablib.devices.IMAQdx package

### Submodules

## pylablib.devices.IMAQdx.IMAQdx module

**class** pylablib.devices.IMAQdx.IMAQdx.TCameraInfo(*name, type, version, flags, serial\_number, bus, vendor, model, camera\_file, attr\_url*)

Bases: `tuple`

**attr\_url**

**bus**

**camera\_file**

**flags**

**model**

**name**

**serial\_number****type****vendor****version**`pylablib.devices.IMAQdx.IMAQdx.list_cameras(connected=True, desc=True)`

List all cameras available through IMAQdx interface

If `desc==True`, return complete camera descriptions; otherwise, simply return the names.`pylablib.devices.IMAQdx.IMAQdx.get_cameras_number()`

Get number of connected dx cameras

**class** `pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute(sid, name)`Bases: `object`

Object representing an IMAQdx camera parameter.

Allows to query and set values and get additional information. Usually created automatically by an `IMAQdxCamera` instance, but could be created manually.**Parameters**

- **sid** – camera session ID
- **name** – attribute text name

**name**

attribute name

**kind**

attribute kind; can be "u32", "i64", "f64", "str", "enum", "bool", "command", or "blob"

**display\_name**

attribute display name (short description name)

**tooltip**

longer attribute description

**description**full attribute description (usually, same as *tooltip*)**units**

attribute units (if applicable)

**visibility**

attribute visibility ("simple", "intermediate", or "advanced")

**readable**

whether attribute is readable

**Type**`bool`**writable**

whether attribute is writable

**Type**`bool`

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**inc**

minimal attribute increment value (if applicable)

**Type**

float or int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**update\_limits()**

Update minimal and maximal attribute limits and return tuple (min, max, inc)

**truncate\_value(value)**

Truncate value to lie within attribute limits

**get\_value(enum\_as\_str=True)**

Get attribute value.

If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.**set\_value(value, truncate=True)**

Get attribute value.

If `truncate==True`, automatically truncate value to lie within allowed range.**class** pylablib.devices.IMAQdx.IMAQdx.TDeviceInfo(*vendor, model, serial\_number, bus\_type*)

Bases: tuple

**bus\_type****model****serial\_number****vendor**

```
class pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera(name='cam0', mode='controller',
                                                    visibility='advanced')
```

Bases: [IROICamera](#), [IAttributeCamera](#)

Generic IMAQdx camera interface.

#### Parameters

- **name** – interface name (can be learned by [list\\_cameras\(\)](#); usually, but not always, starts with "cam")
- **mode** – connection mode; can be "controller" (full control) or "listener" (only reading)
- **visibility** – attribute visibility when listing attributes; can be "simple", "intermediate" or "advanced" (higher mode exposes more attributes).

```
Error = <Mock name='mock.IMAQdxError' id='140527637626256'>
```

```
TimeoutError = <Mock spec='str' id='140527643143568'>
```

```
open()
```

Open connection to the camera

```
close()
```

Close connection to the camera

```
reset()
```

Reset connection to the camera

```
is_opened()
```

Check if the device is connected

```
post_open()
```

Additional setup after camera opening

```
get_attribute_value(name, error_on_missing=True, default=None, enum_as_str=True)
```

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not `None`, assume that `error_on_missing==False`. If *name* points at a dictionary branch, return a dictionary with all values in this branch. If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

```
set_attribute_value(name, value, truncate=True, error_on_missing=True)
```

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If `truncate==True`, truncate value to lie within attribute range.

```
get_all_attribute_values(root="", enum_as_str=True, ignore_errors=True)
```

Get values of all attributes with the given *root*

```
set_all_attribute_values(settings, root="", truncate=True)
```

Set values of all attributes with the given *root*.

If `truncate==True`, truncate value to lie within attribute range.

**get\_device\_info()**

Get camera information.

Return tuple (vendor, model, serial\_number, bus\_type).

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi(hstart=0, hend=None, vstart=0, vend=None)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**class CallbackManager**

Bases: [object](#)

**get\_callback\_ptr()****register(sid)****reset()****start()****stop()****get\_nbuff()****setup\_acquisition(mode='sequence', nframes=100)**

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that [IMAQdxCamera.acquisition\\_in\\_progress\(\)](#) would still return True in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.



**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**refresh\_acquisition(*delay=0.005*)**

Stop and restart the acquisition, waiting *delay* seconds in between

**enable\_raw\_readout(*enable='rows', bytes\_per\_pixel=None, bytes\_per\_image=None*)**

Enable raw frame transfer.

Should be used if the camera uses unsupported pixel format. Can be "frame" (return the whole frame as a 1D "u1" numpy array), "rows" (return a 2D array, where each row corresponds to a single image row), or False (convert to image data, or raise an error if the format is not supported; default). In addition, for cameras which incorrectly implement "PayloadSize" parameter, one can explicitly specify the number of bytes per pixel (possibly fractional) which will be used to calculate the total byte size of the frame, or the total number of bytes per image (if specified, takes priority over *bytes\_per\_pixel*). Both *bytes\_per\_pixel* and *bytes\_per\_image* only apply if *enable* is set to "frame" or "rows".

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {*name*: *value*}

**get\_all\_attributes(*copy=False*)**

Return a dictionary of all available attributes.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute(*name, error\_on\_missing=True*)**

Get the camera attribute with the given name

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (*first* inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(key, value)

Set the value of a settings parameter

**set\_frame\_format**(fmt)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(fmt, include\_fields=None)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(period=1)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(indexing)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(timeout=5.0, return\_info=False)

Snap a single frame

**wait\_for\_frame**(since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (timeout, frame\_timeout), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

```
class pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera(name='cam0', mode='controller',
                                                         visibility='advanced',
                                                         small_packet=False)
```

Bases: [IMAQdxCamera](#)

LAN-controlled IMAQdx camera.

Compared to the standard camera, has an option of automatically switching to a smaller TCP/IP packet size (can be useful if the PC network adapter can't handle jumbo packets).

#### Parameters

- **name** – interface name (can be learned by `list_cameras()`; usually, but not always, starts with "cam")
- **mode** – connection mode; can be "controller" (full control) or "listener" (only reading)
- **visibility** – default attribute visibility when listing attributes; can be "simple", "intermediate" or "advanced" (higher mode exposes more attributes).
- **small\_packet** – if True, automatically set small packet size (1500 bytes).

#### `post_open()`

Additional setup after camera opening

#### `class CallbackManager`

Bases: `object`

`get_callback_ptr()`

`get_nbuff()`

`register(sid)`

`reset()`

`start()`

`stop()`

`Error = <Mock name='mock.IMAQdxError' id='140527637626256'>`

#### `FrameTransferError`

alias of `DefaultFrameTransferError`

`TimeoutError = <Mock spec='str' id='140527643143568'>`

#### `acquisition_in_progress()`

Check if acquisition is in progress

#### `apply_settings(settings)`

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

#### `clear_acquisition()`

Clear acquisition settings

#### `close()`

Close connection to the camera

#### `enable_raw_readout(enable='rows', bytes_per_pixel=None, bytes_per_image=None)`

Enable raw frame transfer.

Should be used if the camera uses unsupported pixel format. Can be "frame" (return the whole frame as a 1D "u1" numpy array), "rows" (return a 2D array, where each row corresponds to a single image row), or False (convert to image data, or raise an error if the format is not supported; default). In addition, for cameras which incorrectly implement "PayloadSize" parameter, one can explicitly specify the number

of bytes per pixel (possibly fractional) which will be used to calculate the total byte size of the frame, or the total number of bytes per image (if specified, takes priority over *bytes\_per\_pixel*). Both *bytes\_per\_pixel* and *bytes\_per\_image* only apply if *enable* is set to "frame" or "rows".

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attribute\_values**(root="", enum\_as\_str=True, ignore\_errors=True)

Get values of all attributes with the given root

**get\_all\_attributes**(copy=False)

Return a dictionary of all available attributes.

If copy==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute**(name, error\_on\_missing=True)

Get the camera attribute with the given name

**get\_attribute\_value**(name, error\_on\_missing=True, default=None, enum\_as\_str=True)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and error\_on\_missing==True, raise error; otherwise, return default. If default is not None, assume that error\_on\_missing==False. If name points at a dictionary branch, return a dictionary with all values in this branch. If enum\_as\_str==True, return enum-style values as strings; otherwise, return corresponding integer values.

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info()**

Get camera information.

Return tuple (vendor, model, serial\_number, bus\_type).

**get\_device\_variable**(key)

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by *get\_frame\_info\_fields()*; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame

format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

#### **get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

#### **get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

#### **get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

#### **get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

#### **get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

#### **get\_new\_images\_range()**

Get the range of the new images.

Return tuple (`first`, `last`) with images range (first inclusive). If no images are available, return `None`. If some images were in the buffer were overwritten, exclude them from the range.

#### **get\_roi()**

Get current ROI.

Return tuple (`hstart`, `hend`, `vstart`, `vend`). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

#### **get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (`hlim`, `vlim`), where each element is in turn a limit 5-tuple (`min`, `max`, `pstep`, `sstep`, `maxbin`) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**is\_opened**()

Check if the device is connected

**open**()

Open connection to the camera

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.



**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**refresh\_acquisition**(*delay=0.005*)

Stop and restart the acquisition, waiting *delay* seconds in between

**reset**()

Reset connection to the camera

**set\_all\_attribute\_values**(*settings, root="", truncate=True*)

Set values of all attributes with the given *root*.

If `truncate==True`, truncate value to lie within attribute range.

**set\_attribute\_value**(*name, value, truncate=True, error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If `truncate==True`, truncate value to lie within attribute range.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**setup\_acquisition**(*mode='sequence', nframes=100*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that `IMAQdxCamera.acquisition_in_progress()` would still return `True` in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(*\*args, \*\*kwargs*)

Start acquisition.

Can take the same keyword parameters as `:meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is `None`). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==`True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

## Module contents

### pylablib.devices.KJL package

#### Submodules

#### pylablib.devices.KJL.base module

**exception** pylablib.devices.KJL.base.**KJLError**

Bases: *DeviceError*

Generic KJL device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.KJL.base.**KJLBackendError**(*exc*)

Bases: *KJLError*, *DeviceBackendError*

Generic KJL backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.KJL.base.**TKJL300DeviceInfo**(*swver*)

Bases: *tuple*

**swver**

**class** pylablib.devices.KJL.base.**KJL300**(*conn*, *addr=1*)

Bases: *ICommBackendWrapper*

KJL300 series pressure gauge.

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **addr** – RS485 address (required both for RS-485 and for RS-232 communication; factory default is 1)

#### Error

alias of *KJLError*

**comm**(*msg*)

Send a command to the device

**query**(*msg*)

**get\_device\_info()**

Get device info (a tuple (swver))

**reset(confirm\_addr=False)**

Reset the controller.

If `confirm_addr==True`, set current RS485 address again (required for resetting after some commands).

**get\_pressure()**

Get current pressure in Pa

**get\_relay\_setpoints(relay=1)**

Get relay setpoints (in Pa).

*relay* is the relay index (either 1 or 2). Return tuple (on, off) for on-below and off-above pressures (on is always smaller than off)

**set\_relay\_setpoints(relay=1, on=None, off=None, reset=True)**

Set relay setpoints (in Pa).

*relay* is the relay index (either 1 or 2). *on* and *off* are on-below and off-above pressures (on is always smaller than off). If `reset==True`, reset the device after changing the setpoints (required to take effect). None values are left unchanged.

**set\_zero(pressure=0)**

Set vacuum calibration point (in Pa)

**set\_span(pressure=100000.0)**

Set atmosphere calibration point (in Pa)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Keithley package

#### Submodules

#### pylablib.devices.Keithley.base module

**exception** pylablib.devices.Keithley.base.**GenericKeithleyError**

Bases: [\*DeviceError\*](#)

Generic Keithley error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Keithley.base.**GenericKeithleyBackendError**(*exc*)

Bases: [\*GenericKeithleyError\*](#), [\*DeviceBackendError\*](#)

Keithley backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.devices.Keithley.multimeter module**

```
class pylablib.devices.Keithley.multimeter.TGenericFunctionParameters(rng, resolution, autorng)
```

Bases: [tuple](#)

**autorng**

**resolution**

**rng**

```
class pylablib.devices.Keithley.multimeter.TFrequencyFunctionParameters(rng, aperture)
```

Bases: [tuple](#)

**aperture**

**rng**

```
class pylablib.devices.Keithley.multimeter.TConfigurationParameters(function, rng, resolution)
```

Bases: [tuple](#)

**function**

**resolution**

**rng**

```
class pylablib.devices.Keithley.multimeter.TAveragingParameters(mode, count, enabled)
```

Bases: [tuple](#)

**count**

**enabled**

**mode**

```
class pylablib.devices.Keithley.multimeter.Keithley2110(addr)
```

Bases: [SCPIDevice](#)

Keithley 2110 bench-top multimeter.

**Parameters**

**addr** – device address (usually a VISA name).

**Error**

alias of [GenericKeithleyError](#)

**ReraiseError**

alias of [GenericKeithleyBackendError](#)

**get\_function**(channel='primary')

Get measurement function for the given measurement channel ("primary" or "secondary", or "all" for both channels)

**set\_function**(function, channel='primary', reset\_secondary=True)

Set measurement function for the given measurement channel ("primary", "secondary", or "all" for both channels).

If `reset_secondary==True` and the primary function is changed, set the secondary function to "none" to avoid conflicts.

**get\_vcr\_function\_parameters**(*function=None*)

Get parameters for the given voltage, current or resistance measurement function.

Supported functions are "volt\_dc", "volt\_ac", "curr\_dc", "curr\_ac", "res", and "fres". Return tuple (*rng*, *resolution*, *autorng*) with, correspondingly, measurement range, resolution, and whether autorange is enabled.

**get\_cap\_function\_parameters**(*function=None*)

Get parameters for the given capacitance measurement function.

The only supported function is "cap". Return tuple (*rng*, *autorng*) with, correspondingly, measurement range and whether autorange is enabled.

**get\_freq\_function\_parameters**(*function=None*)

Set parameters for the given frequency or period measurement function.

Supported functions are "freq\_volt", "freq\_curr", "per\_volt", "per\_curr". Return tuple (*rng*, *aperture*) with, correspondingly, measurement range, and the averaging aperture.

**get\_function\_parameters**(*function=None*)

Get function parameters for any supported function.

Result depends on the function kind. See [get\\_vcr\\_function\\_parameters\(\)](#), [get\\_cap\\_function\\_parameters\(\)](#) and [get\\_freq\\_function\\_parameters\(\)](#) for details.

**set\_vcr\_function\_parameters**(*function=None*, *rng=None*, *resolution=None*, *autorng=None*)

Set parameters for the given voltage, current or resistance measurement function.

Supported functions are "volt\_dc", "volt\_ac", "curr\_dc", "curr\_ac", "res", and "fres". *rng*, *resolution* and *autorng* are correspondingly, measurement range, resolution, and whether autorange is enabled. *rng* and *resolution* can also have values "min", "max" or "def" for, correspondingly, minimal possible, maximal possible, and default value.

**set\_cap\_function\_parameters**(*function=None*, *rng=None*, *autorng=None*)

Set parameters for the given capacitance measurement function.

The only supported function is "cap". *rng* and *autorng* are correspondingly, measurement range and whether autorange is enabled. *rng* can also have values "min", "max" or "def" for, correspondingly, minimal possible, maximal possible, and default value.

**set\_freq\_function\_parameters**(*function=None*, *rng=None*, *aperture=None*)

Set parameters for the given frequency or period measurement function.

Supported functions are "freq\_volt", "freq\_curr", "per\_volt", "per\_curr". *rng* and *aperture* are correspondingly, measurement range and the averaging aperture. *rng* and *aperture* can also have values "min", "max" or "def" for, correspondingly, minimal possible, maximal possible, and default value.

**set\_function\_parameters**(*function=None*, *\*\*kwargs*)

Set function parameters for any supported function.

Arguments depend on the function kind. See [set\\_vcr\\_function\\_parameters\(\)](#), [set\\_cap\\_function\\_parameters\(\)](#) and [set\\_freq\\_function\\_parameters\(\)](#) for details.

**get\_configuration**()

Get current measurement configuration on the primary channel.

Return tuple (*function*, *rng*, *resolution*) with, correspondingly, measurement function, measurement range and resolution.

**set\_configuration**(*function=None, rng=None, resolution=None*)

Set current measurement configuration on the primary channel.

*function*, *rng* and *resolution* are, correspondingly, measurement function, measurement range and resolution.

**get\_reading**(*channel='primary'*)

Initiate and return the reading of the given measurement channel ("primary", "secondary", or "all" for both channels)

**get\_averaging\_parameters**()

Get result averaging parameters.

Return tuple (mode, count, enabled) with, correspondingly, averaging mode ("moving" or "repeat"), number of counts to average, and whether it is enabled.

**setup\_averaging**(*mode=None, count=None, enabled=None*)

Set result averaging parameters.

*mode*, *count* and *enabled* are, correspondingly, averaging mode ("moving" or "repeat"), number of counts to average, and whether it is enabled.

### BackendError

alias of *DeviceBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.



**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, `"*RST"` command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with `;` delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either `'sync'` (perform `wait_sync()`), `'dev'` (perform `wait_dev()`) or `'none'` (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with `","`.
- **arg\_type** (*str*) – Argument type. Can be `'raw'` (in which case data is sent raw), `'string'`, `'int'`, `'float'`, `'bool'`, a format string (such as `'{: .3f}'`) or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string `'1;2'`); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with `","`.
- **unit** (*str*) – If not `None`, use it as a unit to append after the value.

- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if `True`, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (`False` by default).
- **read\_echo** (*bool*) – If `True`, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.Lakeshore package

#### Submodules

#### pylablib.devices.Lakeshore.base module

**exception** `pylablib.devices.Lakeshore.base.LakeshoreError`

Bases: `DeviceError`

Generic Lakeshore devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Lakeshore.base.LakeshoreBackendError`(*exc*)

Bases: `LakeshoreError`, `DeviceBackendError`

Generic Lakeshore backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.devices.Lakeshore.base.TLakeshore218AnalogSettings`(*bipolar*, *mode*, *channel*, *source*, *high\_value*, *low\_value*, *man\_value*)

Bases: `tuple`

**bipolar**

**channel**

**high\_value**

**low\_value**

**man\_value**

**mode**

**source**

**class** pylablib.devices.Lakeshore.base.**TLakeshore218FilterSettings**(*enabled, points, window*)

Bases: [tuple](#)

**enabled**

**points**

**window**

**class** pylablib.devices.Lakeshore.base.**TLakeshore218CurveHeader**(*name, serial, fmt, limit, coeff*)

Bases: [tuple](#)

**coeff**

**fmt**

**limit**

**name**

**serial**

**class** pylablib.devices.Lakeshore.base.**Lakeshore218**(*conn*)

Bases: [SCPIDevice](#)

Lakeshore 218 temperature controller.

The channels are enumerated from 1 to 8 and are split into 2 groups: "A" for 1-4 and "B" for 5-8.

#### **Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

#### **Error**

alias of [LakeshoreError](#)

#### **ReraiseError**

alias of [LakeshoreBackendError](#)

**is\_enabled**(*channel*)

Check if a given channel is enabled

**set\_enabled**(*channel, enabled=True*)

Enable or disable a given channel

**get\_sensor\_type**(*group*)

Get sensor type for a given group ("A" for sensors 1-4 or "B" for sensors 5-8).

For types, see INTYPE command description in the Lakeshore 218 programming manual.

**set\_sensor\_type**(*group*, *sensor\_type*)

Set sensor type for a given group ("A" for sensors 1-4 or "B" for sensors 5-8).

For types, see INTYPE command description in the Lakeshore 218 programming manual.

**get\_sensor\_curve\_index**(*channel*)

Get sensor curve index for a given channel (1 to 8).

For curve descriptions, see INCRV command description in the Lakeshore 218 programming manual.

**set\_sensor\_curve\_index**(*channel*, *index*)

Get sensor curve index for a given channel (1 to 8).

For curve descriptions, see INCRV command description in the Lakeshore 218 programming manual.

**get\_curve\_header**(*index*)

Get header of a given curve (1-9 or 21-28).

Return tuple (*name*, *serial*, *fmt*, *limit*, *coeff*). For values descriptions, see CRVHDR command description in the Lakeshore 218 programming manual.

**set\_curve\_header**(*index*, *name=None*, *serial=None*, *fmt=None*, *limit=None*, *coeff=None*)

Set header of a given user curve (21-28).

For values descriptions, see CRVHDR command description in the Lakeshore 218 programming manual.

**get\_curve**(*index*, *trim\_zeros=True*)

Get values of a given curve (1-9 or 21-28).

Return 2-column numpy array with up to 200 points, where the first column is sensor reading, and the second is temperature; for associated sensor units, see [get\\_curve\\_header\(\)](#). If *trim\_zeros==True*, trim the trailing zero-valued points. Note, that it takes about 10 seconds to complete.

**set\_curve**(*index*, *curve*)

Set values of a given user curve (21-28).

*curve* is a 2-column numpy array with up to 200 points, where the first column is sensor reading, and the second is temperature; for associated sensor units, see [get\\_curve\\_header\(\)](#). Note, that it takes about 20 seconds to complete.

**get\_temperature**(*channel*)

Get readings (in Kelvin) on a given channel (1 to 8)

**get\_all\_temperatures**()

Get readings (in Kelvin) on all channels

**get\_sensor\_reading**(*channel*)

Get readings (in sensor units) on a given channel (1 to 8)

**get\_all\_sensor\_readings**()

Get readings (in sensor units) on all channels

**get\_analog\_output\_settings**(*output*)

Get analog output settings for a given output (1 or 2).

For parameters, see [setup\\_analog\\_output\(\)](#) and ANALOG command description in the Lakeshore 218 programming manual.

**setup\_analog\_output**(*output*, *bipolar=None*, *mode=None*, *channel=None*, *source=None*, *high\_value=None*, *low\_value=None*, *man\_value=None*)

Setup analog output settings for a given output (1 or 2).

For parameters, see `ANALOG` command description in the Lakeshore 218 programming manual. Value of `None` means keeping the current parameter value.

**set\_analog\_output\_value**(*output*, *value*, *bipolar=False*, *enabled=True*)

Set manual analog output value.

A simplified version of `setup_analog_output()`.

**get\_analog\_output**(*output*)

Get value (in percents of the total range) at a given output (1 or 2)

**get\_filter\_settings**(*channel*)

Get input filter settings for a given channel (1 to 8).

For parameters, see `setup_filter()` and `FILTER` command description in the Lakeshore 218 programming manual.

**setup\_filter**(*channel*, *enabled=None*, *points=None*, *window=None*)

Setup input filter settings for a given channel (1 to 8).

For parameters, see `FILTER` command description in the Lakeshore 218 programming manual. Value of `None` means keeping the current parameter value.

### **BackendError**

alias of `DeviceBackendError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {`name`: `value`} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type='string'*, *delay=0.0*, *timeout=None*, *read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If `one_line==True`, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, `"*ESR?"` command)

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes).

If `include_header==True`, return the data with the header; otherwise, return only the content. If `flush_term==True`, flush the following line to skip terminator characters after the binary data, which are added by some devices. `timeout` overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If `new_instrument==True`, create a new backend instance. If `ignore_error==True`, ignore errors on closing.

**reset**()

Reset the device (by default, `"*RST"` command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with `;` delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either `'sync'` (perform `wait_sync()`), `'dev'` (perform `wait_dev()`) or `'none'` (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with `" , "`.
- **arg\_type** (*str*) – Argument type. Can be `'raw'` (in which case data is sent raw), `'string'`, `'int'`, `'float'`, `'bool'`, a format string (such as `'{: .3f}'`) or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'`



with `arg=[1,2]` will produce a string `'1;2'`; if a list of types is used, each element of `arg` is converted using the corresponding type, and the result is joined with `","`.

- **unit** (*str*) – If not `None`, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (`false_value`, `true_value`) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if `True`, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (`False` by default).
- **read\_echo** (*bool*) – If `True`, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

```
class pylablib.devices.Lakeshore.base.TLakeshore370RangeSettings(exc_mode, exc_range,
                                                                res_range, autorange, enable)
```

Bases: *tuple*

**autorange**

**enable**

**exc\_mode**

**exc\_range**

**res\_range**

```
class pylablib.devices.Lakeshore.base.TLakeshore370AnalogSettings(bipolar, mode, channel,
                                                                source, high_value,
                                                                low_value, man_value)
```

Bases: *tuple*

**bipolar**

**channel**

**high\_value**

**low\_value**

**man\_value**

**mode**

**source**

```
class pylablib.devices.Lakeshore.base.TLakeshore370FilterSettings(enabled, settle_time, window)
```

Bases: *tuple*

**enabled**

**settle\_time**

**window**

**class** `pylablib.devices.Lakeshore.base.Lakeshore370(conn)`

Bases: [`SCPIDevice`](#)

Lakeshore 370 resistance bridge / temperature controller.

All channels are enumerated from 0.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of [`LakeshoreError`](#)

**ReraiseError**

alias of [`LakeshoreBackendError`](#)

**get\_temperature(channel)**

Get temperature readings (in K) on a given channel

**get\_resistance(channel)**

Get resistance readings (in Ohm) on a given channel

**get\_sensor\_power(channel)**

Get dissipated power (in W) on a given channel

**select\_channel(channel)**

Select measurement channel

**get\_channel()**

Get current measurement channel

**get\_channel\_range\_settings(channel)**

Setup the current measurement channel range parameters.

For parameters, see [`setup\_channel\_range\(\)`](#) and RDGRNG command description in the Lakeshore 370 programming manual.

**setup\_channel\_range(channel=None, exc\_mode='v', exc\_range=1, res\_range=22, autorange=True, enable=True)**

Setup the measurement channel range (all channels by default).

*exc\_mode* is the excitation mode ("i" or "v"), *exc\_range* is the excitation range (1 is smallest), *res\_range* is the resistance range (1 is smallest). For range descriptions, see Lakeshore 370 programming manual.

**get\_analog\_output\_settings(output)**

Get analog output settings for a given output (1 or 2).

For parameters, see [`setup\_analog\_output\(\)`](#) and ANALOG command description in the Lakeshore 370 programming manual.

**setup\_analog\_output(output, bipolar=None, mode=None, channel=None, source=None, high\_value=None, low\_value=None, man\_value=None)**

Setup analog output settings for a given output (1 or 2).

For parameters, see ANALOG command description in the Lakeshore 370 programming manual. Value of None means keeping the current parameter value.

**set\_analog\_output\_value(output, value, bipolar=False, enabled=True)**

Set manual analog output value.

A simplified version of [`setup\_analog\_output\(\)`](#).

**get\_analog\_output**(*output*)

Get value (in percents of the total range) at a given output (1 or 2)

**get\_filter\_settings**(*channel*)

Get input filter settings for a given channel (1 to 16).

For parameters, see [setup\\_filter\(\)](#) and FILTER command description in the Lakeshore 370 programming manual.

**setup\_filter**(*channel*, *enabled=None*, *settle\_time=None*, *window=None*)

Setup input filter settings for a given channel (1 to 16).

For parameters, see FILTER command description in the Lakeshore 370 programming manual. Value of None means keeping the current parameter value.

**BackendError**

alias of [DeviceBackendError](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type='string'*, *delay=0.0*, *timeout=None*, *read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {**name**: **value**} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {**name**: **value**} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (*value*, *unit*), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type*='sync', *timeout*=None, *wait\_callback*=None)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout*=None, *wait\_callback*=None)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg*=None, *arg\_type*=None, *unit*=None, *bool\_selector*=None, *wait\_sync*=None, *read\_echo*=False, *read\_echo\_delay*=0.0)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.

- **read\_echo\_delay** (*float*) – The delay between write and read if read\_echo==True.

## Module contents

### pylablib.devices.LaserQuantum package

#### Submodules

#### pylablib.devices.LaserQuantum.base module

**exception** pylablib.devices.LaserQuantum.base.**LaserQuantumError**

Bases: *DeviceError*

Generic Laser Quantum devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.LaserQuantum.base.**LaserQuantumBackendError**(*exc*)

Bases: *LaserQuantumError*, *DeviceBackendError*

Generic Laser Quantum backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.LaserQuantum.base.**TDeviceInfo**(*serial, software\_version, cal\_date*)

Bases: *tuple*

**cal\_date**

**serial**

**software\_version**

**class** pylablib.devices.LaserQuantum.base.**TWorkHours**(*psu, laser\_enabled, laser\_threshold*)

Bases: *tuple*

**laser\_enabled**

**laser\_threshold**

**psu**

**class** pylablib.devices.LaserQuantum.base.**TTemperatures**(*head, psu*)

Bases: *tuple*

**head**

**psu**

**class** `pylablib.devices.LaserQuantum.base.Finesse(conn)`

Bases: *ICommBackendWrapper*

Laser Quantum Finesse pump laser.

**Parameters**

**conn** – serial connection parameters (usually port)

**Error**

alias of *LaserQuantumError*

**query**(*comm*, *reply\_lines=1*)

Send a query to the device and read the reply.

*reply\_lines* specify the number of lines to read as a reply (almost all queries have only one line).

**get\_device\_info**()

Get device information (serial, software\_version, cal\_date)

**get\_work\_hours**()

Get the work hours (PSU run time, laser run time, laser above threshold time)

**get\_temperatures**()

Get device status, head temperature, and PSU temperature

**get\_output\_status**()

Get output status.

Can be "enabled" or "disabled".

**get\_interlock\_status**()

Get manual interlock status

**get\_shutter\_status**()

Get the shutter status

**is\_shutter\_opened**()

Check if shutter is opened

**set\_shutter**(*opened=True*)

Open or close the shutter

**is\_enabled**()

Check if the output is enabled

**enable**(*enabled=True*)

Turn the output on or off

**get\_output\_power**()

Get the output power (in Watts)

**get\_output\_setpoint**()

Get the output setpoint power (in Watts)

**set\_output\_power**(*level*)

Set the output power setpoint (in Watts)

**get\_current()**

Get the laser drive current (in %)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)



## Module contents

### pylablib.devices.Leybold package

#### Submodules

#### pylablib.devices.Leybold.base module

**exception** pylablib.devices.Leybold.base.**LeyboldError**

Bases: *DeviceError*

Generic Leybold device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Leybold.base.**LeyboldBackendError**(*exc*)

Bases: *LeyboldError*, *DeviceBackendError*

Generic Leybold backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Leybold.base.**TDeviceInfo**(*sensor, page, swver*)

Bases: *tuple*

**page**

**sensor**

**swver**

**class** pylablib.devices.Leybold.base.**TUpdateValue**(*value, display\_units, status, error, device\_info*)

Bases: *tuple*

**device\_info**

**display\_units**

**error**

**status**

**value**

**class** pylablib.devices.Leybold.base.GenericITR(*conn*)

Bases: [\*ICommBackendWrapper\*](#)

Generic Leybold ITR pressure gauge.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of [\*LeyboldError\*](#)

**get\_update**(*refresh=True*)

Get device state update.

Return tuple (value, display\_units, status, error, device\_info), where value is the pressure in Pa, display\_units are display units ("pa", "mbar", or "torr"), status is the devices status (e.g., emission status), error is the device error ("ok" if no errors), and device\_info is a tuple (sensor, page, swver) with the sensor kind ID, data page, and software version.

If refresh==True, get the latest update value; otherwise, get the latest read value.

**send\_command**(*byte1, byte2, byte3*)

Send command to the device.

Arguments represent the three command bytes. Values of these bytes for different commands are described in the manual.

**get\_device\_info**()

Get device info.

Return tuple (sensor, page, swver) with the sensor kind ID, data page, and software version.

**get\_units**()

Get device readout units ("mbar", "pa", or "torr")

**get\_pressure**(*display\_units=False*)

Get pressure.

If display\_units==False, return result in Pa; otherwise, use display units obtained using [\*get\\_units\(\)\*](#).

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting include=-10 queries all available variables, which is equivalent to include="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.Leybold.base.TITR90Status(*emission, atm\_adj*)

Bases: [tuple](#)

**atm\_adj**

**emission**

**class** pylablib.devices.Leybold.base.ITR90(*conn*)

Bases: [GenericITR](#)

Leybold ITR90 pressure gauge.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**set\_units(units, store=True)**

Get device readout units ("mbar", "pa", or "torr").

If *store==True*, store the value in the non-volatile power-independent memory.

**start\_degas()**

Start degas (turns off automatically after 3 minutes)

**stop\_degas()**

Stop degas

**Error**

alias of [LeyboldError](#)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_info()**

Get device info.

Return tuple (sensor, page, swver) with the sensor kind ID, data page, and software version.

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_pressure(display\_units=False)**

Get pressure.

If *display\_units==False*, return result in Pa; otherwise, use display units obtained using [get\\_units\(\)](#).

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_units()**

Get device readout units ("mbar", "pa", or "torr")

**get\_update(refresh=True)**

Get device state update.

Return tuple (value, display\_units, status, error, device\_info), where value is the pressure in Pa, display\_units are display units ("pa", "mbar", or "torr"), status is the devices status (e.g., emission status), error is the device error ("ok" if no errors), and device\_info is a tuple (sensor, page, swver) with the sensor kind ID, data page, and software version.

If *refresh==True*, get the latest update value; otherwise, get the latest read value.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**send\_command**(*byte1, byte2, byte3*)

Send command to the device.

Arguments represent the three command bytes. Values of these bytes for different commands are described in the manual.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.LighthousePhotonics package

#### Submodules

#### pylablib.devices.LighthousePhotonics.base module

**exception** `pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsError`

Bases: *DeviceError*

Generic Lighthouse Photonics devices error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsBackendError`(*exc*)

Bases: *LighthousePhotonicsError, DeviceBackendError*

Generic Lighthouse Photonics backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

```
class pylablib.devices.LighthousePhotonics.base.TDeviceInfo(product, version, serial,  
                                                         configuration)
```

Bases: `tuple`

**configuration**

**product**

**serial**

**version**

```
class pylablib.devices.LighthousePhotonics.base.TWorkHours(controller, laser)
```

Bases: `tuple`

**controller**

**laser**

```
class pylablib.devices.LighthousePhotonics.base.SproutG(conn)
```

Bases: `ICommBackendWrapper`

Lighthouse Photonics Sprout G laser.

**Parameters**

**conn** – serial connection parameters (usually port)

**Error**

alias of `LighthousePhotonicsError`

```
query(comm, allowed_replies=('0',))
```

Send a query to the device and parse the reply

```
get_device_info()
```

Get device information (product name, product version, serial number, configuration)

```
get_work_hours()
```

Return device operation hours (controller on) and run hours (laser on)

```
get_warning_status()
```

Get device warnings

```
get_interlock_status()
```

Get manual interlock status

```
get_shutter_status()
```

Get manual shutter status ("open" or "close")

```
get_output_mode()
```

Get output mode.

Can be "on", "off", "idle" (power standby mode), "calibrate", "interlock" (manual interlock is off), "warmup" (warmup mode), or "calibration" (calibration mode).

```
set_output_mode(mode='on')
```

Set output mode.

*mode* can be "on", "off", "idle" (power standby mode), or "calibrate" (calibration mode).

**is\_enabled()**

Check if the output is on (idle or warmup don't count as on)

**enable(enabled=True)**

Turn the output on or off

**get\_output\_power()**

Set the actual output power (in Watts)

**get\_output\_setpoint()**

Get the output setpoint power (in Watts)

**set\_output\_power(level)**

Get the output power setpoint (in Watts)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Lumel package

#### Submodules

#### pylablib.devices.Lumel.base module

**class** pylablib.devices.Lumel.base.TDeviceInfo(*model*)

Bases: [tuple](#)

**model**

**class** pylablib.devices.Lumel.base.LumelRE72Controller(*conn*, *daddr=1*)

Bases: [GenericModbusRTUDevice](#)

Lumel RE72 temperature controller.

#### Parameters

- **conn** – serial connection parameters for RS485 adapter (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 9600, 8, 'N', 1))
- **daddr** – default device Modbus address

**get\_device\_info**()

Return device info as a tuple (**model**)

**get\_reg**(*address*, *kind='auto'*)

Get value of a register at the given address.

*kind* is a register kind and can be "int" (2-byte signed integer), "uint" (2-byte unsigned integer), "float" (4-byte float), or "auto" (either signed integer or float depending on the address).

**set\_reg**(*address*, *value*)

Set value of an integer register at the given address

**get\_measurementf**()

Return measurement value as a floating point number.

The result is returned in the current display units.

**get\_setpointf**(*setpoint=None*)

Get setpoint value as a floating point number.

The result is returned in the current display units. *setpoint* specifies the setpoint kind and can be None (current), 1, or 2.



**get\_outputf**(*output=1*)

Get output value in percents.

*output* specifies the output channel and can be 1 or 2.

**get\_measurementi**()

Return measurement value as an integer number

The result is returned in the current display units. For temperature units (C and F) this value is degrees multiplied by 10, while for the physical units (A, V) this relation is determined by the decimal point position.

**get\_setpointi**(*setpoint=None*)

Get setpoint value as an integer point number.

The result is returned in the current display units. For temperature units (C and F) this value is degrees multiplied by 10, while for the physical units (A, V) this relation is determined by the decimal point position. *setpoint* specifies the setpoint kind and can be *None* (current), or an integer from 1 to 4.

**set\_setpointi**(*value, setpoint=None*)

Get setpoint value as an integer point number.

The result is returned in the current display units. For temperature units (C and F) this value is degrees multiplied by 10, while for the physical units (A, V) this relation is determined by the decimal point position. *setpoint* specifies the setpoint kind and can be *None* (current), or an integer from 1 to 4.

## Error

alias of [\*ModbusError\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**mb\_get\_default\_address()**

Get device address used by default in Modbus methods

**mb\_get\_device\_id(daddr=None)**

Get Modbus device ID (function 17)

**mb\_read\_coils(address, quantity=1, daddr=None)**

Read Modbus one-bit discrete coils with the given starting address and quantity

**mb\_read\_discrete\_inputs(address, quantity, daddr=None)**

Read Modbus one-bit discrete inputs with the given starting address and quantity

**mb\_read\_holding\_registers(address, quantity, daddr=None)**

Read Modbus two-byte holding registers with the given starting address and quantity

**mb\_read\_input\_registers(address, quantity, daddr=None)**

Read Modbus two-byte input registers with the given starting address and quantity

**mb\_scan\_devices(daddrs='all', timeout=0.1, func=1, payload=b'')**

Scan for devices on the bus by sending a specified command and waiting for the reply.

*daddrs* is a list of addresses to check ("all" means all addresses from 1 to 247 inclusive) *timeout* is the timeout to wait for each device reply. *func* and *payload* specify the message to send (by default, 'read coil' command with no arguments, which should always return an error) Since the addresses are polled consecutively, this function can take a long time (~25s for the default settings).

**mb\_set\_default\_address(daddr)**

Set device address used by default in Modbus methods

**mb\_using\_address(daddr)**

Context manager for temporary using a different default device address

**mb\_write\_multiple\_coils(address, value, quantity=None, daddr=None)**

Write multiple Modbus one-bit discrete coils with the given starting address and quantity.

*value* is a bytes object with the bit values listed LSB first.

**mb\_write\_multiple\_holding\_registers(address, value, daddr=None)**

Write a multiple Modbus two-byte holding registers at the given address.

*value* is a bytes object with the values listed LSB first.

**mb\_write\_single\_coil(address, value, daddr=None)**

Write a single Modbus one-bit discrete coil at the given address

**mb\_write\_single\_holding\_register(address, value, daddr=None)**

Write a single Modbus two-byte holding register at the given address

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.M2 package

#### Submodules

#### pylablib.devices.M2.base module

**exception** pylablib.devices.M2.base.**M2Error**

Bases: *DeviceError*

Generic M2 error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.M2.base.**M2ParseError**(\*args, code=None)

Bases: *M2Error*

M2 parse error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.M2.base.**M2CommunicationError**(exc)

Bases: *M2Error*, *DeviceBackendError*

M2 network communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.M2.base.ICEBlocDevice(addr, port, timeout=5.0, start\_link=True)

Bases: *IDevice*

Generic M2 Ice Bloc device.

#### Parameters

- **addr** (*str*) – IP address of the Ice Bloc device.
- **port** (*int*) – port of the Ice Bloc device.
- **timeout** (*float*) – default timeout of synchronous operations.
- **start\_link** (*bool*) – if True, initialize device link on creation.

#### Error

alias of *M2Error*

#### ReraiseError

alias of *M2CommunicationError*

#### BackendError

alias of *OSError*

#### open()

Open the connection

#### close()

Close the connection

#### is\_opened()

Check if the device is connected

#### set\_timeout(timeout)

Set timeout for connecting or sending/receiving

#### flush()

Flush read buffer

#### noreply(exhaust\_when\_done=False)

Context manager within which the code switches to the no-reply mode, where it does not wait for a reply to certain commands (usually element setting commands). This allows for faster command issuing, but ignores possible errors returned by the commands. If `exhaust_when_done==True`, receive all sent replies upon exiting the context; otherwise, receive them the next time a communication with the device is done.

#### query(op, params, reply\_op='auto', report=False, allow\_noreply=False)

Send a query using the standard device interface.

`reply_op` is the name of the reply operation (by default, its the operation name plus `"_reply"`). If `report==True`, request completion report (does not apply to all operation). If `allow_noreply==True`, allow skipping the reply, which allows for faster consecutive command issuing; this only works if the no-reply mode is also activated using `noreply()`. Return tuple (`command`, `args`) with the reply command name and the corresponding arguments (in no-reply mode return `(None, None)`).

#### update\_reports(timeout=0.0, ignore\_replies=None, max\_replies=None)

Check for fresh operation reports.

By default, only receive reports and raise an error on replies; if `ignore_replies` is supplies, it is a list of replies which do not raise an error. If `max_replies` is supplied, it is the maximal number of replies to read before stopping (by default, no limit, i.e., wait a read leads to a timeout).

**get\_last\_report**(*op*)

Get the latest report for the given operation

**check\_report**(*op*)

Check and return the latest report for the given operation

**wait\_for\_report**(*op*, *error\_msg=None*, *timeout=None*)

Wait for a report for the given operation

*error\_msg* specifies the exception message if the report results in an error.

**start\_link**()

Initialize device link (called automatically on creation)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

## pylablib.devices.M2.emm module

**class** pylablib.devices.M2.emm.EMM(*addr*, *port*, *timeout=5.0*, *start\_link=True*)

Bases: [ICEBlocDevice](#)

M2 EMM Ice Bloc device.

### Parameters

- **addr** (*str*) – IP address of the Ice Bloc device.
- **port** (*int*) – port of the Ice Bloc device.
- **timeout** (*float*) – default timeout of synchronous operations.

- **start\_link** (*bool*) – if True, initialize device link on creation.

**get\_laser\_status()**

Get the device system status

**fine\_tune\_wavelength**(*wavelength*, *beam*='visible', *sync*=True, *timeout*=None)

Fine-tune the wavelength.

If *sync*==True, wait until the operation is complete (might take from several seconds up to several minutes).

**check\_fine\_tuning\_report()**

Check wavelength fine-tuning report

Return "success" or "fail" if the operation is complete, or None if it is still in progress.

**wait\_for\_fine\_tuning**(*timeout*=None)

Wait until wavelength fine-tuning is complete

**is\_fine\_tuning()**

check if fine tuning is in progress

**get\_fine\_tuning\_status()**

Get fine-tuning status.

Return either "idle" (no tuning or locking) or "active" (tuning in progress).

**get\_fine\_wavelength()**

Get fine-tuned wavelength

**stop\_fine\_tuning()**

Stop fine wavelength tuning

**setup\_terascan**(*scan\_type*, *scan\_range*, *rate*, *trunc\_rate*=True)

Setup terascan.

#### Parameters

- **scan\_type** (*str*) – scan type. Can be "medium" (BRF+etalon, rate from 100 GHz/s to 1 GHz/s), "fine" (all elements, rate from 20 GHz/s to 1 MHz/s), "ir\_medium" or "ir\_fine" (same as "medium" or "fine", but defined for the IR laser)
- **scan\_range** (*tuple*) – tuple (start, stop) with the scan range (in Hz).
- **rate** (*float*) – scan rate (in Hz/s).
- **trunc\_rate** (*bool*) – if True, truncate the scan rate to the nearest available rate (otherwise, incorrect rate would raise an error).

**start\_terascan**(*scan\_type*, *sync*=False, *sync\_done*=False)

Start terascan.

Scan parameters are set up separately using `setup_terascan()`. Scan type can be "medium" (BRF+etalon, rate from 100 GHz/s to 1 GHz/s), "fine" (all elements, rate from 20 GHz/s to 1 MHz/s), "ir\_medium" or "ir\_fine" (same as "medium" or "fine", but defined for the IR laser) If *sync*==True, wait until the scan is set up (not until the whole scan is complete). If *sync\_done*==True, wait until the whole scan is complete (not recommended, as it can take hours).

**enable\_terascan\_updates**(*enable=True, update\_period=0.01, update\_delay=0*)

Enable sending periodic terascan updates.

If enabled, laser will send updates in the beginning and in the end of every terascan segment. If *update\_period!=0*, it will also send updates every *update\_period* percents of the segment (this option is not currently supported by M2 firmware).

**check\_terascan\_update**()

Check the latest terascan update.

Return *None* if none are available, or a dictionary {"wavelength":*current\_wavelength*, "activity":*op*}, where *op* is "scanning" (scanning in progress), "stitching" (stitching in progress), or "repeat" (segment is repeated).

**wait\_for\_terascan\_update**()

Wait until a new terascan update is available

**check\_terascan\_start\_report**()

Check report on terascan start.

Return "success" or "fail" if the operation is complete, or *None* if it is still in progress.

**stop\_terascan**(*scan\_type, sync=False*)

Stop terascan of the given type.

If *sync==True*, wait until the operation is complete.

**get\_terascan\_status**(*scan\_type*)

Get status of a terascan of a given type (or all statuses if *scan\_type=="all"*).

**Return a dictionary with 3 items:**

"current": current laser frequency (or *None* if no scan is in progress) "range": tuple with the full scan range (or *None* if no frequency is available) "status": can be "stopped" (scan is not in progress), "scanning" (scan is in progress), or "stitching" (scan is in progress, but currently stitching)

**stop\_all\_operation**(*repeated=True, attempt=0*)

Stop all laser operations (tuning and scanning).

If *repeated==True*, repeat trying to stop the operations until succeeded (more reliable, but takes more time). If *attempt>0*, it can supply the number of already tried attempts to stop (with *repeated=False*); the more attempts failed, the more drastic measures will be taken to stop (e.g., initialize short terascan) Return *True* if the operation is success and *False* otherwise.

**BackendError**

alias of *OSError*

**Error**

alias of *M2Error*

**ReraiseError**

alias of *M2CommunicationError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**check\_report**(*op*)

Check and return the latest report for the given operation

**close()**

Close the connection

**flush()**

Flush read buffer

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_last\_report(op)**

Get the latest report for the given operation

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**noreply(exhaust\_when\_done=False)**

Context manager within which the code switches to the no-reply mode, where it does not wait for a reply to certain commands (usually element setting commands). This allows for faster command issuing, but ignores possible errors returned by the commands. If *exhaust\_when\_done==True*, receive all sent replies upon exiting the context; otherwise, receive them the next time a communication with the device is done.

**open()**

Open the connection

**query(op, params, reply\_op='auto', report=False, allow\_noreply=False)**

Send a query using the standard device interface.

*reply\_op* is the name of the reply operation (by default, its the operation name plus "\_reply"). If *report==True*, request completion report (does not apply to all operation). If *allow\_noreply==True*, allow skipping the reply, which allows for faster consecutive command issuing; this only works if the no-reply mode is also activated using [noreply\(\)](#). Return tuple (command, args) with the reply command name and the corresponding arguments (in no-reply mode return (None, None)).

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**set\_timeout(timeout)**

Set timeout for connecting or sending/receiving



**start\_link()**

Initialize device link (called automatically on creation)

**update\_reports**(*timeout=0.0, ignore\_replies=None, max\_replies=None*)

Check for fresh operation reports.

By default, only receive reports and raise an error on replies; if `ignore_replies` is supplies, it is a list of replies which do not raise an error. If `max_replies` is supplied, it is the maximal number of replies to read before stopping (by default, no limit, i.e., wait a read leads to a timeout).

**wait\_for\_report**(*op, error\_msg=None, timeout=None*)

Wait for a report for the given operation

*error\_msg* specifies the exception message if the report results in an error.

**pylablib.devices.M2.solstis module**

**class** pylablib.devices.M2.solstis.**Solstis**(*addr, port, timeout=5.0, start\_link=True, use\_websocket='auto', use\_cavity=True*)

Bases: [\*ICEBlocDevice\*](#)

M2 Solstis Ice Bloc device.

**Parameters**

- **addr** (*str*) – IP address of the Ice Bloc device.
- **port** (*int*) – port of the Ice Bloc device.
- **timeout** (*float*) – default timeout of synchronous operations.
- **start\_link** (*bool*) – if True, initialize device link on creation.
- **use\_websocket** (*bool*) – if True, use websocket interface (same as used by the web interface) for additional functionality (wavemeter connection, etalon value, improved operation stopping); "auto" enables it if websocket package is installed, and disables otherwise
- **use\_cavity** – if False and any reference cavity methods are used, either ignore them, or use closest available methods instead

**connect\_wavemeter**(*sync=True*)

Connect to the wavemeter (if `sync==True`, wait until the connection is established)

**disconnect\_wavemeter**(*sync=True*)

Disconnect from the wavemeter (if `sync==True`, wait until the connection is broken)

**is\_wavemeter\_connected**()

Check if the wavemeter is connected

**get\_system\_status**()

Get the device system status

**get\_full\_web\_status**()

Get full websocket status.

Return a large dictionary containing all the information available in the web interface.

**get\_full\_fine\_tuning\_status**()

Get full fine-tuning status (see M2 Solstis JSON protocol manual for "poll\_wave\_m" command)

**lock\_wavemeter**(*lock=True, sync=True, error\_on\_fail=True*)

Lock or unlock the laser to the wavemeter (if *sync==True*, wait until the operation is complete)

**is\_wavemeter\_lock\_on**()

Check if the laser is locked to the wavemeter

**fine\_tune\_wavelength**(*wavelength, sync=True, timeout=None*)

Fine-tune the wavelength.

Only works if the wavemeter is connected. If *sync==True*, wait until the operation is complete (might take from several seconds up to several minutes).

**check\_fine\_tuning\_report**()

Check wavelength fine-tuning report

Return "success" or "fail" if the operation is complete, or *None* if it is still in progress.

**wait\_for\_fine\_tuning**(*timeout=None*)

Wait until wavelength fine-tuning is complete

**get\_fine\_tuning\_status**()

Get fine-tuning status.

Return either "idle" (no tuning or locking), "nolink" (no wavemeter link), "tuning" (tuning in progress), or "locked" (tuned and locked to the wavemeter).

**get\_fine\_wavelength**()

Get fine-tuned wavelength.

Only works if the wavemeter is connected.

**stop\_fine\_tuning**()

Stop fine wavelength tuning

**coarse\_tune\_wavelength**(*wavelength, sync=True*)

Coarse-tune the wavelength.

Only works if the wavemeter is disconnected. If *sync==True*, wait until the operation is complete.

**get\_full\_coarse\_tuning\_status**()

Get full coarse-tuning status (see M2 M2 Solstis JSON protocol manual for "poll\_move\_wave\_t" command)

**get\_coarse\_tuning\_status**()

Get coarse-tuning status.

Return either "done" (tuning is done), "tuning" (tuning in progress), or "fail" (tuning failed).

**get\_coarse\_wavelength**()

Get course-tuned wavelength.

Only works if the wavemeter is disconnected.

**stop\_coarse\_tuning**()

Stop coarse wavelength tuning

**tune\_etalon**(*value, sync=True*)

Tune the etalon to *value* percent.

Only works if the wavemeter is disconnected. If *sync==True*, wait until the operation is complete.

**lock\_etalon**(*sync=True*)

Lock the etalon.

If *sync==True*, wait until the operation is complete.

**unlock\_etalon**(*sync=True*)

Unlock the etalon .

If *sync==True*, wait until the operation is complete. Automatically unlock the reference cavity first (otherwise the operation fails).

**get\_etalon\_lock\_status**()

Get etalon lock status.

Return either "off" (lock is off), "on" (lock is on), "debug" (lock in debug condition), "error" (lock had an error), "search" (lock is searching), or "low" (lock is off due to low output).

**tune\_laser\_resonator**(*value*, *fine=False*, *sync=True*)

Tune the laser cavity to *value* percent.

If *fine==True*, adjust fine tuning; otherwise, adjust coarse tuning. Only works if the wavemeter is disconnected. If *sync==True*, wait until the operation is complete.

**tune\_reference\_cavity**(*value*, *fine=False*, *sync=True*)

Tune the reference cavity to *value* percent.

If *fine==True*, adjust fine tuning; otherwise, adjust coarse tuning. Only works if the wavemeter is disconnected. If *sync==True*, wait until the operation is complete. If reference cavity is disabled by setting *use\_cavity=False* on creation, do nothing.

**lock\_reference\_cavity**(*sync=True*)

Lock the laser to the reference cavity.

Automatically lock etalon first (otherwise the operation fails). If *sync==True*, wait until the operation is complete. If reference cavity is disabled by setting *use\_cavity=False* on creation, do nothing.

**unlock\_reference\_cavity**(*sync=True*)

Unlock the laser from the reference cavity.

If *sync==True*, wait until the operation is complete. If reference cavity is disabled by setting *use\_cavity=False* on creation, do nothing.

**get\_reference\_cavity\_lock\_status**()

Get the reference cavity lock status.

Return either "off" (lock is off), "on" (lock is on), "debug" (lock in debug condition), "error" (lock had an error), "search" (lock is searching), "low" (lock is off due to low output), or "disabled" (reference cavity is disabled by setting *use\_cavity=False* on creation).

**setup\_terascan**(*scan\_type*, *scan\_range*, *rate*, *trunc\_rate=True*)

Setup terascan.

#### Parameters

- **scan\_type** (*str*) – scan type. Can be "medium" (BRF+etalon, rate from 100 GHz/s to 1 GHz/s), "fine" (all elements, rate from 20 GHz/s to 1 MHz/s), or "line" (all elements, rate from 20 GHz/s to 50 kHz/s).
- **scan\_range** (*tuple*) – tuple (start, stop) with the scan range (in Hz).
- **rate** (*float*) – scan rate (in Hz/s).

- **trunc\_rate** (*bool*) – if True, truncate the scan rate to the nearest available rate (otherwise, incorrect rate would raise an error).

If reference cavity is disabled by setting `use_cavity=False` on creation and `scan_type` is "line", use "fine" instead.

**start\_terascan**(*scan\_type, sync=False, sync\_done=False*)

Start terascan.

Scan parameters are set up separately using `setup_terascan()`. Scan type can be "medium" (BRF+etalon, rate from 100 GHz/s to 1 GHz/s), "fine" (all elements, rate from 20 GHz/s to 1 MHz/s), or "line" (all elements, rate from 20 GHz/s to 50 kHz/s). If reference cavity is disabled by setting `use_cavity=False` on creation and `scan_type` is "line", use "fine" instead. If `sync==True`, wait until the scan is set up (not until the whole scan is complete). If `sync_done==True`, wait until the whole scan is complete (not recommended, as it can take hours).

**enable\_terascan\_updates**(*enable=True, update\_period=0*)

Enable sending periodic terascan updates.

If enabled, laser will send updates in the beginning and in the end of every terascan segment. If `update_period!=0`, it will also send updates every `update_period` percents of the segment (this option is not currently supported by M2 firmware).

**check\_terascan\_update**()

Check the latest terascan update.

Return None if none are available, or a dictionary {"wavelength":current\_wavelength, "activity":op}, where op is "scanning" (scanning in progress), "stitching" (stitching in progress), "finished" (scan is finished), or "repeat" (segment is repeated).

**wait\_for\_terascan\_update**()

Wait until a new terascan update is available

**check\_terascan\_start\_report**()

Check report on terascan start.

Return "success" or "fail" if the operation is complete, or None if it is still in progress.

**stop\_terascan**(*scan\_type, sync=False*)

Stop terascan of the given type.

If reference cavity is disabled by setting `use_cavity=False` on creation and `scan_type` is "line", use "fine" instead. If `sync==True`, wait until the operation is complete.

**get\_terascan\_status**(*scan\_type, web\_status=True*)

Get status of a terascan of a given type.

**Return a dictionary with 4 items:**

"current": current laser frequency (or None if no scan is in progress) "range": tuple with the full scan range (or None if no frequency is available) "status": can be "stopped" (scan is not in progress), "scanning" (scan is in progress), or "stitching" (scan is in progress, but currently stitching) "web": whether scan is running in web interface (some failure modes still report "scanning" through the usual interface); only available if the laser web connection is on and if `web_status==True`.

If reference cavity is disabled by setting `use_cavity=False` on creation and `scan_type` is "line", use "fine" instead.

**start\_fast\_scan**(*scan\_type, width, period, sync=False, setup\_locks=True*)

Setup and start fast scan.

### Parameters

- **scan\_type** (*str*) – scan type. Can be "cavity\_continuous", "cavity\_single", "cavity\_triangular", "etalon\_continuous", "etalon\_single", "resonator\_continuous", "resonator\_single", "resonator\_ramp", "resonator\_triangular", "ecd\_continuous", "ecd\_ramp", or "fringe\_test" (see M2 Solstis JSON protocol manual for details)
- **width** (*float*) – scan width (in Hz).
- **period** (*float*) – scan time/period (in s).
- **sync** (*bool*) – if True, wait until the scan is set up (not until the whole scan is complete).
- **setup\_locks** (*bool*) – if True, automatically setup etalon and reference cavity locks in the appropriate states for etalon, cavity, or resonator scans.

If reference cavity is disabled by setting `use_cavity=False` on creation, use resonator scans instead of cavity scans.

### **check\_fast\_scan\_start\_report()**

Check fast scan start report.

Return "success" or "fail" if the operation is complete, or None if it is still in progress.

### **stop\_fast\_scan(scan\_type, return\_to\_start=True, sync=False)**

Stop fast scan of the given type.

If reference cavity is disabled by setting `use_cavity=False` on creation, use resonator scans instead of cavity scans. If `return_to_start==True`, return to the center frequency after stopping; otherwise, stay at the current instantaneous frequency. If `sync==True`, wait until the operation is complete.

### **get\_fast\_scan\_status(scan\_type)**

Get status of a fast scan of a given type.

#### **Return dictionary with 2 items:**

"status": can be "stopped" (scan is not in progress), "scanning" (scan is in progress). "value": current tuner value (in percent); does not necessary correspond to the scan progress.

If reference cavity is disabled by setting `use_cavity=False` on creation, use resonator scans instead of cavity scans.

### **stop\_scan\_web(scan\_type)**

Stop scan of the current type (terascan or fine scan) using web interface.

More reliable than native programming interface, but requires activated web interface. If reference cavity is disabled by setting `use_cavity=False` on creation, use resonator scans instead of cavity scans.

### **stop\_all\_operation(repeated=True, attempt=0)**

Stop all laser operations (tuning and scanning).

More reliable than native programming interface, but requires activated web interface. If `repeated==True`, repeat trying to stop the operations until succeeded (more reliable, but takes more time). If `attempt>0`, it can supply the number of already tried attempts to stop (with `repeated=False`); the more attempts failed, the more drastic measures will be taken to stop (e.g., initialize short terascan or a fast scan, cycle wavemeter connection, etc.) Return True if the operation is success and False otherwise.

### **BackendError**

alias of `OSError`

**Error**

alias of *M2Error*

**ReraiseError**

alias of *M2CommunicationError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**check\_report**(*op*)

Check and return the latest report for the given operation

**close**()

Close the connection

**flush**()

Flush read buffer

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_last\_report**(*op*)

Get the latest report for the given operation

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**noreply**(*exhaust\_when\_done=False*)

Context manager within which the code switches to the no-reply mode, where it does not wait for a reply to certain commands (usually element setting commands). This allows for faster command issuing, but ignores possible errors returned by the commands. If *exhaust\_when\_done==True*, receive all sent replies upon exiting the context; otherwise, receive them the next time a communication with the device is done.

**open**()

Open the connection

**query**(*op*, *params*, *reply\_op*='auto', *report*=False, *allow\_noreply*=False)

Send a query using the standard device interface.

*reply\_op* is the name of the reply operation (by default, its the operation name plus "\_reply"). If *report*==True, request completion report (does not apply to all operation). If *allow\_noreply*==True, allow skipping the reply, which allows for faster consecutive command issuing; this only works if the no-reply mode is also activated using [noreply\(\)](#). Return tuple (*command*, *args*) with the reply command name and the corresponding arguments (in no-reply mode return (None, None)).

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_timeout**(*timeout*)

Set timeout for connecting or sending/receiving

**start\_link**()

Initialize device link (called automatically on creation)

**update\_reports**(*timeout*=0.0, *ignore\_replies*=None, *max\_replies*=None)

Check for fresh operation reports.

By default, only receive reports and raise an error on replies; if *ignore\_replies* is supplies, it is a list of replies which do not raise an error. If *max\_replies* is supplied, it is the maximal number of replies to read before stopping (by default, no limit, i.e., wait a read leads to a timeout).

**wait\_for\_report**(*op*, *error\_msg*=None, *timeout*=None)

Wait for a report for the given operation

*error\_msg* specifies the exception message if the report results in an error.

## Module contents

### pylablib.devices.Mightex package

#### Submodules

#### pylablib.devices.Mightex.MightexSSeries module

**class** `pylablib.devices.Mightex.MightexSSeries.TCameraInfo`(*idx*, *model*, *serial*)

Bases: `tuple`

**idx**

**model**

**serial**

**class** `pylablib.devices.Mightex.MightexSSeries.LibraryController`(*lib*)

Bases: `LibraryController`

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None

**get\_opened\_num()**

Get number of opened devices

**open()**

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None

**preinit()**

Pre-initialize the library, if it hasn't been done already

**shutdown()**

Close all opened connections and shutdown the library

**temp\_open()**

Context for temporarily opening a new device connection

`pylablib.devices.Mightex.MightexSSeries.restart_lib()`

`pylablib.devices.Mightex.MightexSSeries.list_cameras()`

List all cameras available through Mightex S-series interface

`pylablib.devices.Mightex.MightexSSeries.get_cameras_number()`

Get number of connected Mightex S-series cameras

**class** `pylablib.devices.Mightex.MightexSSeries.TDeviceInfo(model, serial)`

Bases: `tuple`

**model**

**serial**

**class** `pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera(idx=1)`

Bases: `IBinROICamera`, `IExposureCamera`

Generic Mightex S Series camera interface.

**Parameters**

**idx** – camera index among the cameras listed using `list_cameras()`, starting with 1

**Error**

alias of `MightexError`

**TimeoutError**

alias of `MightexTimeoutError`

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected



**get\_device\_info()**

Get camera information.

Return tuple (model, serial).

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend, hbin, vbin). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi(hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_exposure()**

Get current exposure

**set\_exposure(exposure)**

Set camera exposure

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (exposure, frame\_period).

**get\_pixel\_clock()**

Get pixel clock speed ("slow", "medium", or "fast")

**set\_pixel\_clock(pixel\_clock)**

Set pixel clock speed ("slow", "medium", or "fast")

**get\_hblanking()**

Get hblanking speed ("normal", "longer", or "longest")

**set\_hblanking(hblanking)**

Set hblanking speed ("normal", "longer", or "longest")

**send\_software\_trigger()**

Send software trigger signal

**class ReceiveLooper**

Bases: `object`

**enable\_callback()**

Register and enable the frame callback

**disable\_callback()**

Stop and deregister the frame callback

**is\_looping()**

Check if the loop is running

**get\_status()**

Get the current loop status, which is the tuple (acquired,)

**allocate**(*nbuff*, *size*)

Allocate given number of buffers of the given size

**deallocate()**

Deallocate the buffers

**setup\_acquisition**(*mode*='sequence', *nframes*=100)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frame buffers.

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**FrameTransferError**

alias of `DefaultFrameTransferError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

## pylablib.devices.Mightex.base module

**exception** `pylablib.devices.Mightex.base.MightexError`

Bases: `DeviceError`

Generic Mightex error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Mightex.base.MightexTimeoutError`

Bases: `MightexError`

Mightex frame timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## Module contents

### pylablib.devices.Modbus package

#### Submodules

### pylablib.devices.Modbus.modbus module

**exception** `pylablib.devices.Modbus.modbus.ModbusError`

Bases: `DeviceError`

Generic Modbus device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Modbus.modbus.**ModbusBackendError**(*exc*)

Bases: [ModbusError](#), [DeviceBackendError](#)

Generic Modbus backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Modbus.modbus.**TModbusFrame**(*address, function, data*)

Bases: [tuple](#)

**address**

**data**

**function**

**class** pylablib.devices.Modbus.modbus.**GenericModbusRTUDevice**(*conn, daddr=1, conn\_defaults=('COM1', 9600)*)

Bases: [ICommBackendWrapper](#)

Generic Modbus-connected RTU protocol device.

#### Parameters

- **conn** – serial connection parameters (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 9600, 8, 'N', 1))
- **daddr** – default device address
- **conn\_defaults** – default connection parameters (baud rate, parity bits, etc.)

#### Error

alias of [ModbusError](#)

**mb\_get\_default\_address()**

Get device address used by default in Modbus methods

**mb\_set\_default\_address**(*daddr*)

Set device address used by default in Modbus methods

**mb\_using\_address**(*daddr*)

Context manager for temporary using a different default device address

**mb\_read\_coils**(*address, quantity=1, daddr=None*)

Read Modbus one-bit discrete coils with the given starting address and quantity

**mb\_read\_discrete\_inputs**(*address, quantity, daddr=None*)

Read Modbus one-bit discrete inputs with the given starting address and quantity

**mb\_read\_holding\_registers**(*address, quantity, daddr=None*)

Read Modbus two-byte holding registers with the given starting address and quantity

**mb\_read\_input\_registers**(*address, quantity, daddr=None*)

Read Modbus two-byte input registers with the given starting address and quantity

**mb\_write\_single\_coil**(*address, value, daddr=None*)

Write a single Modbus one-bit discrete coil at the given address

**mb\_write\_single\_holding\_register**(*address, value, daddr=None*)

Write a single Modbus two-byte holding register at the given address

**mb\_write\_multiple\_coils**(*address, value, quantity=None, daddr=None*)

Write multiple Modbus one-bit discrete coils with the given starting address and quantity.

*value* is a bytes object with the bit values listed LSB first.

**mb\_write\_multiple\_holding\_registers**(*address, value, daddr=None*)

Write a multiple Modbus two-byte holding registers at the given address.

*value* is a bytes object with the values listed LSB first.

**mb\_get\_device\_id**(*daddr=None*)

Get Modbus device ID (function 17)

**mb\_scan\_devices**(*daddrs='all', timeout=0.1, func=1, payload=b''*)

Scan for devices on the bus by sending a specified command and waiting for the reply.

*daddrs* is a list of addresses to check ("all" means all addresses from 1 to 247 inclusive) *timeout* is the timeout to wait for each device reply. *func* and *payload* specify the message to send (by default, 'read coil' command with no arguments, which should always return and error) Since the addresses are polled consecutively, this function can take a long time (~25s for the default settings).

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.



**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.NI package

#### Submodules

#### pylablib.devices.NI.daq module

**exception** pylablib.devices.NI.daq.**NIError**

Bases: *DeviceError*

Generic NI error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.NI.daq.**NIDAQmxError**(*exc*)

Bases: *NIError, DeviceBackendError*

NI DAQmx backend operation error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.NI.daq.**TDeviceInfo**(*name, model, serial\_number*)

Bases: *tuple*

**model**

**name**

**serial\_number**

**class** pylablib.devices.NI.daq.TVoltageOutputClockParameters(*rate, sync\_with\_ai, continuous, samps\_per\_chan, autoloop*)

Bases: [tuple](#)

**autoloop**

**continuous**

**rate**

**samps\_per\_chan**

**sync\_with\_ai**

pylablib.devices.NI.daq.get\_device\_info(*name*)

Get device info.

Return tuple (name, model, serial).

pylablib.devices.NI.daq.list\_devices()

List all connected NI DAQ devices

**class** pylablib.devices.NI.daq.NIDAQ(*dev\_name='dev0', rate=100.0, buffer\_size=100000.0, reset=False*)

Bases: [IDevice](#)

National Instruments DAQ device interface (wrapper around nidaqmx library).

Simplified interface to NI DAQ devices. Supports voltage, digital, and counter inputs (all synchronized to the same clock), and digital and voltage outputs (asynchronous).

#### Parameters

- **dev\_name** (*str*) – root device name.
- **rate** (*float*) – analog input sampling rate (can be adjusted later).
- **buffer\_size** (*int*) – size of the input buffer.
- **reset** (*int*) – if True, reset the device upon connection.

#### Error

alias of [NIError](#)

#### ReraiseError

alias of [NIDAQmxError](#)

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**reset()**

Reset the device. All channels will be removed

**get\_device\_info()**

Get device info.

Return tuple (name, model, serial).

**setup\_clock(rate, src=None)**

Setup analog input clock (which is the main system clock).

If `src==None`, use internal clock with the given rate; otherwise use `src` terminal as a clock source (in this case, `rate` should be higher than the expected source rate).

**get\_clock\_parameters()**

Get analog input clock configuration.

Return tuple (rate, src).

**export\_clock(*terminal*)**

Export system clock to the given terminal (None to disconnect all terminals)

Only terminal one can be active at a time.

**get\_export\_clock\_terminal()**

Return terminal which outputs system clock (None if none is connected)

**add\_voltage\_input(name, channel, rng=(-10, 10), terminal\_cfg='default')**

Add analog voltage input.

Readout is synchronized to the system clock.

**Parameters**

- **name** (*str*) – channel name to refer to it later.
- **channel** (*str*) – terminal name (e.g., "ai0").
- **rng** – voltage range
- **terminal\_cfg** – terminal configuration; can be "default", "rse" (single-ended, referenced to AI SENSE input), "nrse" (single-ended, referenced to AI GND), "diff" (differential), or "pseudodiff" (see NI DAQ manual for details).

**add\_counter\_input(name, counter, terminal, clk\_src='ai/SampleClock', output\_format='rate')**

Add counter input (value is related to the number of counts).

Readout is synchronized to the system clock.

**Parameters**

- **name** (*str*) – channel name.
- **counter** (*str*) – on-board counter name (e.g., "ctr0").
- **terminal** (*str*) – terminal name (e.g., "pfi0").
- **clk\_src** (*str*) – source of the counter sampling clock. By default it is the analog input clock, which requires at least one voltage input channel (could be a dummy channel) to be set up first.
- **output\_format** (*str*) – output format. Can be "acc" (return accumulated number of counts since the sampling start), "diff" (return number of counts passed between

the two consecutive sampling points; essentially, a derivative of "acc"), or "rate" (return count rate based on the "diff" samples).

**add\_clock\_period\_input**(*counter*, *clk\_src*='ai/SampleClock')

Add clock period counter.

Useful when using external sample clock with unknown period. The clock input can be returned during [read\(\)](#) operation, and it is used to calculate counter inputs in "rate" mode. Readout is synchronized to the system clock.

#### Parameters

- **counter** (*str*) – on-board counter name (e.g., "ctr0") to be used for clock measure.
- **clk\_src** (*str*) – source of the counter sampling clock. By default it is the analog input clock, which requires at least one voltage input channel (could be dummy channel) to operate.

**add\_digital\_input**(*name*, *channel*)

Add digital input.

Readout is synchronized to the system clock. :param name: channel name. :type name: str :param channel: terminal name (e.g., "port0/line12"). :type channel: str

**get\_input\_channels**(*include*=('ai', 'ci', 'di'))

Get names of all input channels (voltage input and counter input).

*include* specifies which channel types to include into the list ("ai" for voltage inputs, "ci" for counter inputs, "di" for digital inputs, "cpi" for clock period channel). The channels order is always fixed: first voltage inputs, then counter inputs, then digital inputs.

**get\_voltage\_input\_parameters**()

Get parameters (names, channels, output ranges, and terminal configurations) of all analog voltage input channels

**get\_counter\_input\_parameters**()

Get parameters (names, counters, terminals, clock sources, and output formats) of all counter input channels

**get\_digital\_input\_parameters**()

Get parameters (names and channels) of all digital input channels

**get\_clock\_period\_input\_parameters**()

Get parameters (counter input) of the clock period input channel

**start**(*flush\_read*=0, *finite*=None)

Start the sampling and output task.

*flush\_read* specifies number of samples to read and discard after start. If *finite* is not None, it specifies finite number of sample to acquire before stopping.

If counter channels are used, the first sample is usually unreliable, so *flush\_read*=1 is recommended; however, if exactly *finite* pulses are required at the clock export channel, *flush\_read*=0 is needed (the total number of pulses is *flush\_read*+*finite*).

**stop**()

Stop the sampling task

**is\_running**()

Check if the task is running

**available\_samples()**

Get number of available samples to read (return 0 if the task is not running)

**get\_buffer\_size()**

Get the sampling buffer size

**wait\_for\_sample(num=1, timeout=10.0, wait\_time=0.001)**

Wait until at least *num* samples are available.

If they are not available immediately, loop while checking every *wait\_time* interval until enough samples are accumulated. Return the number of available samples if successful, or 0 if the execution timed out.

**read(n=1, flush\_read=0, timeout=10.0, include=('ai', 'ci', 'di'))**

Read *n* samples. If the task is not running, automatically start before reading and stop after.

**Parameters**

- **n** (*int*) – number of samples to read. If *n* ≤ 0, read all available samples.
- **flush\_read** (*int*) – number of initial samples to skip if the task is currently stopped and needs to be started. If counter channels are used, the first sample is usually unreliable, so *flush\_read*=1 is recommended; however, if exactly *n* pulses are required at the clock export channel, *flush\_read*=0 is needed.
- **include** (*tuple*) – specifies which channel types to include into the list ("ai" for voltage inputs, "ci" for counter inputs, "di" for digital inputs, "cpi" for clock period channel).

**Returns**

2D numpy array of values arranged according to [get\\_input\\_channels\(\)](#) order with the given *include* parameter.

**add\_digital\_output(name, channel)**

Add digital output.

**Parameters**

- **name** (*str*) – channel name.
- **channel** (*str*) – terminal name (e.g., "do0").

**get\_digital\_output\_channels()**

Get names of all digital output channels

**get\_digital\_output\_parameters()**

Get parameters (names and channels) of all digital output channels

**set\_digital\_outputs(names, values)**

Set values of one or several digital outputs.

**Parameters**

- **names** (*str* or [*str*]) – name or list of names of outputs.
- **values** – output value or list of values.

**get\_digital\_outputs(names=None)**

Get values of one or several digital outputs.

**Parameters**

**names** (*str* or [*str*] or *None*) – name or list of names of outputs (*None* means all outputs).

Return list of values ordered by *names* (or by `get_digital_output_channels()` if *names*==None).

**add\_voltage\_output**(*name*, *channel*, *rng*=(-10, 10), *initial\_value*=0.0)

Add analog voltage output.

#### Parameters

- **name** (*str*) – channel name.
- **channel** (*str*) – terminal name (e.g., "ao0").
- **rng** – voltage range.
- **initial\_value** (*float*) – initial output value (has to be initialized).

**get\_voltage\_output\_channels()**

Get names of all analog voltage output channels

**get\_voltage\_output\_parameters()**

Get parameters (names, channels and output ranges) of all analog voltage output channels

**set\_voltage\_outputs**(*names*, *values*, *minsamp*=1, *force\_restart*=True, *single\_shot*=0)

Set values of one or several analog voltage outputs.

#### Parameters

- **names** (*str* or [*str*]) – name or list of names of outputs.
- **values** – output value or list values. These can be single numbers, or arrays if the output clock is setup (see `setup_voltage_output_clock()`). In the latter case it sets up the output waveforms; note that waveforms for all channels must have the same length (a single number signifying a constant output is also allowed) If the analog output is set up to the finite mode (`continuous`==False), the finite waveform output happens right away, with the number of samples determined by *samps\_per\_channel* parameter of `setup_voltage_output_clock()`. In this case, if the supplied waveform is shorter than the number of samples, it gets repeated; if it's longer, it gets cut off.
- **minsamp** – in non-autoloop mode, specifies the minimal number of samples to write to the output buffer; if the length of *values* is less than this number, than the waveform is repeated by a required integer number of times to produce at least *minsamp* samples
- **force\_restart** – if True, restart the output after writing to immediately start outputting the new waveforms; otherwise, add it to the end of the buffer; only applies in non-autoloop mode (autoloop mode always restarts)
- **single\_shot** – specifies some number of samples from the start as “single-shot”, so whenever the waveform is repeated (either to reach *minsamp* samples, or when `fill_voltage_output_buffer()` is called), this part is ignored, and only the rest is repeated

**get\_voltage\_output\_buffer\_fill()**

Get the number of samples still in the output buffer.

Only applies to non-autoloop mode, and return None otherwise.

**fill\_voltage\_output\_buffer**(*minsamp*=1)

Add samples to the output buffer until there are at least *minsamp* samples there.

Only applies to non-autoloop mode, and does nothing otherwise. The added samples are determined based on the last data written by `set_voltage_outputs()` and the *single\_shot* argument specified there.

**get\_voltage\_outputs**(*names=None*)

Get values of one or several analog voltage outputs.

**Parameters**

**names** (*str* or [*str*] or *None*) – name or list of names of outputs (*None* means all outputs).

Return list of values ordered by *names* (or by `get_voltage_output_channels()` if *names*==*None*). For continuous waveforms, return the array containing a single repetition of the waveform. For finite waveforms, repeat the array containing the last outputted waveform.

**setup\_voltage\_output\_clock**(*rate=0, sync\_with\_ai=False, continuous=True, samps\_per\_chan=1000, autoloop=True, minsamp=1*)

Setup analog output clock configuration.

**Parameters**

- **rate** – clock rate; if 0, assume constant voltage output (default)
- **sync\_with\_ai** – if *True*, the clock is synchronized to the analog input clock (the main clock); note that in this case output changes only when the analog read task is running
- **continuous** – if *True*, any written waveform gets repeated continuously; otherwise, it outputs written waveform only once, and then latches the output on the last value
- **samps\_per\_chan** – if *continuous*==*False*, it determines number of samples to output before stopping; otherwise, it determines the size of the output buffer
- **autoloop** – if it is *True*, then the specified output waveforms are automatically repeated to create a periodic output signal (referred to as “regeneration mode” in NI DAQ terminology); otherwise, written output data is “exhausted” once sent to the output, so the application needs to continuously write output waveforms to avoid output buffer from running empty (which causes an error). This mode gives better control over the output and allows to seamlessly adjust it in real time, but it is more demanding on the application.
- **minsamp** – if the waveform has been specified before, this argument sets the minimal number of samples to write to the output buffer after the clock is set up and the output is restarted

**get\_voltage\_output\_clock\_parameters**()

Get analog output clock configuration.

Return tuple (*rate, sync\_with\_ai, continuous, samps\_per\_chan, autoloop*).

**add\_pulse\_output**(*name, counter, terminal, kind='time', on=0.001, off=0.001, clk\_src=None, continuous=True, samps=1000*)

Add counter pulse input.

**Parameters**

- **name** (*str*) – channel name.
- **counter** (*str*) – on-board counter name (e.g., “ctr0”).
- **terminal** (*str*) – output terminal name (e.g., “pfi0”).
- **kind** (*str*) – pulse output kind; can be either “time” (use internal timebase; specify the pulse on and off times in seconds) or “ticks” (use internal or external timebase; specify the pulse on and off times in number of ticks of the clock)

- **on** – on time or number of ticks for the pulse
- **off** – off time or number of ticks for the pulse
- **clk\_src** (*str*) – source of the counter sampling clock. By default it is the device timebase (usually 100MHz); can be a name of an external terminal (e.g., "pfi1"), or "ai" to use the analog input sampling clock
- **continuous** (*bool*) – if **True**, the pulses are generated as long as the output is running; otherwise, output the number of samples specified in *samps* and then stop
- **samps** – number of samples to output if **continuous==False**

**get\_pulse\_output\_channels()**

Get names of all pulse output channels

**get\_pulse\_output\_parameters()**

Get parameters (names, counters, terminals, kinds, on times, off times, clock sources, continuous, number of samples) of all pulse output channels

**set\_pulse\_output** (*name, on=None, off=None, continuous=None, samps=None, terminal=None, restart=True*)

Change pulse output parameters.

Parameter meanings are the same as in [add\\_pulse\\_output\(\)](#). Parameters with values if **None** are left unchanged. If any parameters are not **None**, the output pulse task is stopped before parameter changing. If the task is currently running and **restart==True**, restart the task after changing the parameters.

**start\_pulse\_output** (*names=None, autostop=True*)

Start specified pulse output or a set of outputs (by default, all of them)

**stop\_pulse\_output** (*names=None*)

Stop specified pulse output or a set of outputs (by default, all of them)

**apply\_settings** (*settings*)

Apply the settings.

*settings* is the dict {**name**: **value**} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable** (*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info** (*include=0*)

Get dict {**name**: **value**} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**get\_full\_status** (*include=0*)

Get dict {**name**: **value**} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**get\_settings** (*include=0*)

Get dict {**name**: **value**} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.



**is\_pulse\_output\_running**(*names=None*)

Check if pulse outputs with the given name or set of names are running

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

## Module contents

### pylablib.devices.NKT package

#### Submodules

#### pylablib.devices.NKT.interbus module

**exception** pylablib.devices.NKT.interbus.**InterbusError**

Bases: *DeviceError*

Generic Interbus device error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.NKT.interbus.**InterbusBackendError**(*exc*)

Bases: *InterbusError, DeviceBackendError*

Generic Interbus backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.NKT.interbus.**TInterbusTelegram**(*dest, src, typ, payload*)

Bases: *tuple*

**dest**

**payload**

**src**

**typ**

**class** pylablib.devices.NKT.interbus.**GenericInterbusDevice**(*conn*)

Bases: *ICommBackendWrapper*

Generic Interbus-connected device.

**Parameters**

**conn** – serial connection parameters (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 9600, 8, 'N', 1))

**Error**

alias of *InterbusError*

**ib\_get\_default\_address()**

Get destination address used by default in Interbus methods

**ib\_set\_default\_address(dest)**

Set destination address used by default in Interbus methods

**ib\_using\_address(dest)**

Context manager for temporary using a different default destination address

**ib\_get\_reg(dest, address, dtype='raw', array='auto')**

Get register value at the given destination device and register address.

*dtype* is the register type, which can be "raw" (raw bytes), "str" (string), "u8", "u16", "u32", "i8", "i16", "i32" (different integer values).

**ib\_set\_reg(dest, address, value, dtype='raw', array='auto', echo=True)**

Set register value at the given destination device and register address.

*dtype* is the register type, which can be "raw" (raw bytes), "str" (string), "u8", "u16", "u32", "i8", "i16", "i32" (different integer values).

If *echo*==True, return the subsequent value of the register.

**ib\_scan\_devices(dests='all', timeout=0.05)**

Scan for devices on the bus and return their addresses and types.

*dests* is a list of addresses to check ("all" means all addresses from 1 to 48 inclusive) *timeout* is the timeout to wait for each device reply. *func* and *payload* specify the message to send (by default, 'read coil' command with no arguments, which should always return and error) Since the addresses are polled consecutively, this function can take a long time (~25s for the default settings).

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.NKT.interbus.**IInterbusModule**(*ib\_device, dest*)

Bases: *IDevice*

Specific Interbus module.

Deals with specific registers available for this module.

#### Parameters

- **ib\_device** – instance of the generic Interbus controller used to access the module.
- **dest** – module address on the bus.

**get\_register**(*name*)

Get value of the given register based on its name

**get\_all\_registers**()

Get values of all defined registers

**set\_register**(*name, value*)

Set value of the given register based on its name

**get\_status**()

Get device status as a set of set bits

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**class** pylablib.devices.NKT.interbus.GenericInterbusModule(*ib\_device*, *dest*)

Bases: [\*IInterbusModule\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_all\_registers**()

Get values of all defined registers

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_register**(*name*)

Get value of the given register based on its name

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status**()

Get device status as a set of set bits

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_register**(*name*, *value*)

Set value of the given register based on its name

**class** pylablib.devices.NKT.interbus.SuperKExtremeInterbusModule(*ib\_device*, *dest*)

Bases: [IInterbusModule](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_all\_registers**()

Get values of all defined registers

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_register**(*name*)

Get value of the given register based on its name

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status**()

Get device status as a set of set bits

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_register**(*name, value*)

Set value of the given register based on its name

**class** pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule(*ib\_device, dest*)

Bases: [\*IInterbusModule\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_all\_registers**()

Get values of all defined registers

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_register**(*name*)

Get value of the given register based on its name

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status**()

Get device status as a set of set bits

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_register**(*name*, *value*)

Set value of the given register based on its name

**class** pylablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule(*ib\_device*, *dest*)

Bases: [IInterbusModule](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_all\_registers**()

Get values of all defined registers

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_register**(*name*)

Get value of the given register based on its name

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status**()

Get device status as a set of set bits

**i** = 7**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_register**(*name, value*)

Set value of the given register based on its name

**class** pylablib.devices.NKT.interbus.SuperKSelectInterbusModule(*ib\_device, dest*)

Bases: [\*IInterbusModule\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_all\_registers**()

Get values of all defined registers

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.



**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_register(name)**

Get value of the given register based on its name

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_status()**

Get device status as a set of set bits

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**set\_register(name, value)**

Set value of the given register based on its name

**class** pylablib.devices.NKT.interbus.**InterbusSystem**(conn, modules='auto')

Bases: [GenericInterbusDevice](#)

A collection of NKT modules connected to the same Interbus.

**Parameters**

- **conn** – serial connection parameters (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 9600, 8, 'N', 1))
- **modules** – Interbus modules identifiers; can be "auto" (detect all connected modules), a list of module addresses, or a dictionary {addr: name} of the aliases for the modules (e.g., {'laser':15, 'varia':18})

**m**

dictionary of modules, defined either by their address or by their name (if provided upon creation)

**Error**

alias of [InterbusError](#)

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_all\_module\_registers()**

Get all registers

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**ib\_get\_default\_address()**

Get destination address used by default in Interbus methods

**ib\_get\_reg(dest, address, dtype='raw', array='auto')**

Get register value at the given destination device and register address.

*dtype* is the register type, which can be "raw" (raw bytes), "str" (string), "u8", "u16", "u32", "i8", "i16", "i32" (different integer values).

**ib\_scan\_devices(dests='all', timeout=0.05)**

Scan for devices on the bus and return their addresses and types.

*dests* is a list of addresses to check ("all" means all addresses from 1 to 48 inclusive) *timeout* is the timeout to wait for each device reply. *func* and *payload* specify the message to send (by default, 'read coil' command with no arguments, which should always return and error) Since the addresses are polled consecutively, this function can take a long time (~25s for the default settings).

**ib\_set\_default\_address(dest)**

Set destination address used by default in Interbus methods

**ib\_set\_reg(dest, address, value, dtype='raw', array='auto', echo=True)**

Set register value at the given destination device and register address.

*dtype* is the register type, which can be "raw" (raw bytes), "str" (string), "u8", "u16", "u32", "i8", "i16", "i32" (different integer values).

If *echo==True*, return the subsequent value of the register.

**ib\_using\_address(dest)**

Context manager for temporary using a different default destination address

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Newport package

#### Submodules

#### pylablib.devices.Newport.base module

**exception** pylablib.devices.Newport.base.**NewportError**

Bases: [\*DeviceError\*](#)

Generic Newport device error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Newport.base.**NewportBackendError**(*exc*)

Bases: [\*NewportError\*](#), [\*DeviceBackendError\*](#)

Newport backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## pylablib.devices.Newport.picomotor module

`pylablib.devices.Newport.picomotor.get_usb_devices_number()`

Get the number of controllers connected via USB

`pylablib.devices.Newport.picomotor.muxaddr(*args, **kwargs)`

Multiplex the function over its addr argument

**class** `pylablib.devices.Newport.picomotor.TDeviceInfo(id)`

Bases: `tuple`

`id`

**class** `pylablib.devices.Newport.picomotor.Picomotor8742(conn=0, backend='auto', timeout=5.0, multiaddr=False, scan=True)`

Bases: `ICommBackendWrapper`, `IMultiaxisStage`

Picomotor 8742 4-axis controller.

### Parameters

- **conn** – connection parameters; can be an index (starting from 0) for USB devices, or an IP address (e.g., "192.168.0.2") or host name (e.g., "8742-12345") for Ethernet devices
- **backend** – communication backend; by default, try to determine from the communication parameters
- **timeout** (*float*) – default operation timeout
- **multiaddr** – if `True`, assume that there are several daisy-chained devices connected to the current one; in this case, `get_device_info` and related methods return dictionaries `{addr: value}` for all connected controllers instead of simply values for the given controller
- **scan** – if `True` and `multiaddr==True`, scan for all connected devices (call `scan_devices()`) upon connection

### Error

alias of `NewportError`

**query**(*comm*, *axis=None*, *addr=None*, *read\_reply=None*)

**get\_id**(*addr=None*)

Get the device identification string

**get\_device\_info**(*addr=None*)

Get the device info of the controller board: (*id\_string*,)

**reset**(*addr=None*)

Restart the device.

Reboots the CPU and restores all saved settings from the parameter memory.

**save\_parameters**(*addr=None*)

Store current parameters to the non-volatile memory.

Affects axes speed and acceleration, motor types, and Ethernet parameters.

**restore\_parameters**(*src='memory', addr=None*)

Restore parameters from the non-volatile memory (if *src*=="memory") for factory parameters (if *src*=="factory").

Affects axes speed and acceleration, motor types, and Ethernet parameters.

**scan\_devices**(*reassign='conflict', sync=True*)

Scan for devices connected to the current host device via RS-485 daisy-chaining.

*reassign* controls how device addresses are assigned during the scan; can be "none" (keep current values; can lead to conflicts if several devices have the same address), "conflict" (change conflicting addresses), or "all" (assigned all new addresses in sequence starting from the host)

If *sync*==True, wait until the scan is done (might take several seconds).

**get\_addr\_map**()

Get address map for devices connected to the current host device via RS-485 daisy-chaining.

Return tuple (*addresses*, *conflict*), where *addresses* is the list of all device addresses, and *conflict*==True if there address conflicts (several devices having the same address).

**wait\_for\_scan**(*timeout=10.0*)

Wait for the device connection scan to finish

**get\_addr**(*addr=None*)

Get RS-485 address of the given device (host if *addr* is None)

**set\_addr**(*new\_addr, addr=None*)

Set RS-485 address of the given device (host if *addr* is None)

**get\_ethernet\_parameters**(*addr=None*)

Get Ethernet connection parameters.

Return tuple (*hostname*, *ipaddr*, *ipmode*, *gateway*, *netmask*).

**setup\_ethernet**(*hostname=None, ipmode=None, ipaddr=None, gateway=None, netmask=None, addr=None*)

Setup Ethernet connection parameters.

Any None value remains unchanged. Note that these settings only take effect after saving parameters to the memory ([save\\_parameters\(\)](#)) and restarting the device ([reset\(\)](#)). If the connection is made through Ethernet, then it will likely be invalidated, in which case a new device object with the updated parameters should be created after reset.

**autodetect\_motors**(*addr=None*)

Autodetect connected motors.

The command involves sending single-step commands to the motors, so it requires all axes to be stopped, and it might slightly affect the current position. After the detection the types can be stored in the memory via [save\\_parameters\(\)](#).

**get\_motor\_type**(*axis='all', addr=None*)

Get type of the given axis motor

**set\_motor\_type**(*axis='all', motor\_type='standard', addr=None*)

Manually set type of the given axis motor

**move\_to**(*axis, position, addr=None*)

Move to a given position

**move\_by**(*axis*, *steps*=1, *addr*=None)

Move by a given number of steps

**get\_position**(*axis*='all', *addr*=None)

Get the current axis position

**set\_position\_reference**(*axis*, *position*=0, *addr*=None)

Set the current axis position as a reference (the actual motor position stays the same)

**jog**(*axis*, *direction*, *addr*=0)

Jog a given axis in a given direction.

*direction* can be either "-" (negative) or "+" (positive). The motion continues until it is explicitly stopped.

**is\_moving**(*axis*='all', *addr*=None)

Check if the axis is moving

**wait\_move**(*axis*='all', *addr*=None)

Wait until axis motion is done

**stop**(*axis*='all', *immediate*=False, *addr*=None)

Stop motion of a given axis.

If *immediate*==True make an abrupt stop; otherwise, slow down gradually. Note that immediate stop has to stop all axes simultaneously, so it only takes *axis*=="all".

**get\_velocity\_parameters**(*axis*='all', *addr*=None)

Return velocity parameters (*speed*, *accel*) for the given axis and controller.

*speed* and *accel* denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in steps/s and steps/s<sup>2</sup>.

**setup\_velocity**(*axis*='all', *speed*=None, *accel*=None, *addr*=None)

Setup velocity parameters (*speed*, *accel*) for the given axis and controller.

*speed* and *accel* denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in steps/s and steps/s<sup>2</sup>. None values are left unchanged.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include*=0)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**Module contents****pylablib.devices.OZOptics package****Submodules****pylablib.devices.OZOptics.base module****exception pylablib.devices.OZOptics.base.OZOpticsError**

Bases: [DeviceError](#)

Generic OZOptics devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

args

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.OZOptics.base.OZOpticsBackendError(*exc*)

Bases: *OZOpticsError*, *DeviceBackendError*

Generic OZOptics backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.OZOptics.base.OZOpticsDevice(*conn*, *timeout=20.0*)

Bases: *ICommBackendWrapper*

Generic OZOptics device.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of *OZOpticsError*

**query**(*comm*, *prefix=None*, *prefix\_line=None*, *timeout=None*)

Query the device.

If *prefix* is not *None*, it can specify a string which should be at the beginning of the *prefix\_line* line of the reply. If it is present, it is removed and the rest of that line is returned; otherwise, an error is raised. If *prefix\_line* is *None*, return the first reply line beginning with the given prefix value (or raise an error if not such line is present).

**restart()**

Restart the device

**get\_config()**

Get device configuration

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.



**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.OZOptics.base.TF100(conn, timeout=20.0)

Bases: *OZOpticsDevice*

OZOptics TF100 tunable filter.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**get\_wavelength\_correction()**

Get the current wavelength correction parameters (*shift*, *scale*).

The relation between the set/get wavelength and the wavelength set to the device is calculated as  $\text{device\_wavelength} = \text{set\_wavelength} * \text{scale} + \text{shift}$

**set\_wavelength\_correction(shift=0.0, scale=1.0)**

Set the wavelength correction parameters.

The relation between the set/get wavelength and the wavelength set to the device is calculated as  $\text{device\_wavelength} = \text{set\_wavelength} * \text{scale} + \text{shift}$

**home()**

Home the motor (needs to be called first after startup)

**get\_wavelength()**

Get the currently set wavelength (or None if unknown / not homed)

**set\_wavelength(wavelength)**

Set the current wavelength

**Error**

alias of *OZOpticsError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_config()**

Get device configuration

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**query(comm, prefix=None, prefix\_line=None, timeout=None)**

Query the device.

If *prefix* is not *None*, it can specify a string which should be at the beginning of the *prefix\_line* line of the reply. If it is present, it is removed and the rest of that line is returned; otherwise, an error is raised. If *prefix\_line* is *None*, return the first reply line beginning with the given prefix value (or raise an error if not such line is present).

**restart()**

Restart the device

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** `pylablib.devices.OZOptics.base.DD100`(*conn*, *timeout=20.0*)

Bases: `OZOpticsDevice`

OZOptics DD100 variable attenuator.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**home()**

Home the motor (needs to be called first after startup)

**get\_min\_attenuation()**

Get the minimal possible attenuation (i.e., insertion loss)

**get\_max\_attenuation()**

Get the maximal possible possible attenuation in dB

**get\_attenuation()**

Get the current attenuation in dB

**set\_attenuation**(*att*)

Set the current attenuation in dB

**Error**

alias of `OZOpticsError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_config()**

Get device configuration

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**query(comm, prefix=None, prefix\_line=None, timeout=None)**

Query the device.

If *prefix* is not *None*, it can specify a string which should be at the beginning of the *prefix\_line* line of the reply. If it is present, it is removed and the rest of that line is returned; otherwise, an error is raised. If *prefix\_line* is *None*, return the first reply line beginning with the given prefix value (or raise an error if not such line is present).

**restart()**

Restart the device

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.OZOptics.base.EPC04(conn, timeout=20.0)

Bases: *ICommBackendWrapper*

OZOptics EPC04 polarization controller.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of *OZOpticsError*

**query(comm)****get\_voltages()**

Get all voltages

**set\_voltage**(*channel*, *voltage*)

Set voltage at a given channel (0 through 3)

**set\_all\_voltages**(*voltages*)

Set all channel voltages.

*voltages* is a list of size 4 containing the voltage values.

**step\_voltage**(*channel*, *step*)

Step voltage at the given channel by the given step

**get\_mode**()

Get current operating mode.

Can be "dc" (constant voltage) or "ac" (scrambling).

**set\_mode**(*mode*='dc')

Set current operating mode.

Can be "dc" (constant voltage) or "ac" (scrambling).

**get\_frequencies**()

Get all scrambling frequencies

**set\_frequency**(*channel*, *frequency*)

Set scrambling frequency a given channel (0 through 3)

**set\_all\_frequencies**(*frequencies*)

Set all channel scrambling frequencies.

*frequencies* is a list of size 4 containing the frequency values.

**get\_waveform**()

Get current scrambling waveform.

Can be "sin" (sine wave) or "tri" (triangle wave).

**set\_waveform**(*waveform*)

Set current scrambling waveform.

Can be "sin" (sine wave) or "tri" (triangle wave).

**save\_preset**()

Save current state as a power-up preset

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include*=0)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Omron package

#### Submodules

#### pylablib.devices.Omron.base module

```
class pylablib.devices.Omron.base.TDeviceInfo(model)
```

Bases: `tuple`

`model`

```
class pylablib.devices.Omron.base.OmronE5xCController(conn, daddr=1)
```

Bases: `GenericModbusRTUDevice`

Omron E5\_C temperature controller.

#### Parameters

- **conn** – serial connection parameters for RS485 adapter (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 9600, 8, 'E', 1))
- **daddr** – default device Modbus address

**get\_device\_info()**

Return device info as a tuple (model)

**get\_reg(address, kind='int', nbytes=2)**

Get value of a register at the given address.

*kind* is a register kind and can be "int" (signed integer) or "uint" (unsigned integer). *nbytes* is the size of the register and can be 2 or 4.

**set\_reg(address, value)**

Set value of an integer register at the given address

**get\_measurementi()**

Return measurement value as an integer number

The result is returned in the current display units. For temperature units (C and F) this value is degrees, while for the physical units (A, V) this relation is determined by the decimal point position.

**get\_setpointi()**

Get setpoint value as an integer point number.

The result is returned in the current display units.

**set\_setpointi(value)**

Get setpoint value as an integer point number.

The value is specified and the result is returned in the current display units.

**Error**

alias of *ModbusError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**mb\_get\_default\_address()**

Get device address used by default in Modbus methods

**mb\_get\_device\_id(daddr=None)**

Get Modbus device ID (function 17)

**mb\_read\_coils(address, quantity=1, daddr=None)**

Read Modbus one-bit discrete coils with the given starting address and quantity

**mb\_read\_discrete\_inputs(address, quantity, daddr=None)**

Read Modbus one-bit discrete inputs with the given starting address and quantity

**mb\_read\_holding\_registers(address, quantity, daddr=None)**

Read Modbus two-byte holding registers with the given starting address and quantity

**mb\_read\_input\_registers(address, quantity, daddr=None)**

Read Modbus two-byte input registers with the given starting address and quantity

**mb\_scan\_devices(daddrs='all', timeout=0.1, func=1, payload=b'')**

Scan for devices on the bus by sending a specified command and waiting for the reply.

*daddrs* is a list of addresses to check ("all" means all addresses from 1 to 247 inclusive) *timeout* is the timeout to wait for each device reply. *func* and *payload* specify the message to send (by default, 'read coil' command with no arguments, which should always return an error) Since the addresses are polled consecutively, this function can take a long time (~25s for the default settings).

**mb\_set\_default\_address(daddr)**

Set device address used by default in Modbus methods

**mb\_using\_address(daddr)**

Context manager for temporary using a different default device address

**mb\_write\_multiple\_coils(address, value, quantity=None, daddr=None)**

Write multiple Modbus one-bit discrete coils with the given starting address and quantity.

*value* is a bytes object with the bit values listed LSB first.

**mb\_write\_multiple\_holding\_registers(address, value, daddr=None)**

Write a multiple Modbus two-byte holding registers at the given address.

*value* is a bytes object with the values listed LSB first.

**mb\_write\_single\_coil(address, value, daddr=None)**

Write a single Modbus one-bit discrete coil at the given address

**mb\_write\_single\_holding\_register(address, value, daddr=None)**

Write a single Modbus two-byte holding register at the given address

**open()**

Open the backend



**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Ophir package

#### Submodules

#### pylablib.devices.Ophir.base module

**exception** pylablib.devices.Ophir.base.**OphirError**

Bases: [DeviceError](#)

Generic Ophir device error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Ophir.base.**OphirBackendError**(*exc*)

Bases: [OphirError](#), [DeviceBackendError](#)

Generic Ophir backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Ophir.base.**OphirDevice**(*conn*)

Bases: [ICommBackendWrapper](#)

Generic Ophir device.

#### Parameters

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

#### Error

alias of [OphirError](#)

**query**(*comm*)

Send a query to the device and parse the reply

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.Ophir.base.**TheadInfo**(*type, serial, name, capabilities*)

Bases: `tuple`

**capabilities**

**name**

**serial**

**type**

**class** pylablib.devices.Ophir.base.**TDeviceInfo**(*id, serial, name, rom\_version*)

Bases: `tuple`

**id**

**name**

**rom\_version**

**serial**

**class** pylablib.devices.Ophir.base.**TWavelengthInfo**(*mode, rng, curr\_idx, presets, curr\_wavelength*)

Bases: `tuple`

**curr\_idx**

**curr\_wavelength**

**mode**

**presets**

**rng**

**class** pylablib.devices.Ophir.base.**TRangeInfo**(*curr\_idx, ranges, curr\_range*)

Bases: `tuple`

**curr\_idx**

**curr\_range**

**ranges**

**class** pylablib.devices.Ophir.base.**VegaPowerMeter**(*conn*)

Bases: `OphirDevice`

Ophir Vega power meter.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**get\_head\_info()**

Get head information.

Return tuple (type, serial, name, capabilities).

**get\_device\_info()**

Get device information.

Return tuple (id, serial, name, rom\_version).

**reset()**

Reset the device

**get\_power()**

Get the current power readings.

Return either measured power, or "over", if the power is overrange.

**get\_energy()**

Get the current energy readings.

Return either measured energy, or "over", if the energy is overrange.

**get\_frequency()**

Get the current frequency readings.

Return either measured frequency, or "over", if the power is overrange.

**get\_units()**

Get device reading units

**get\_wavelength\_info()**

Get wavelength setting info.

Return tuple (*mode*, *rng*, *curr\_idx*, *presets*, *curr\_wavelength*), where *mode* is the measurement mode ("continuous" or "discrete"), *rng* is a 2-tuple with the full wavelength range (in m) for continuous mode or a set of all wavelengths for discrete mode, *curr\_idx* is the current wavelength preset index, *presets* is the list of all preset wavelengths (in m) for continuous mode or a set of all wavelengths for discrete mode, and *curr\_wavelength* is the current measurement wavelength (in m) for continuous mode or the current wavelength name for discrete mode.

**get\_wavelength()**

Get current wavelength (in nm)

**set\_wavelength(*wavelength*)**

Set current wavelength (in nm).

*wavelength* is either a wavelength (in m) for the continuous mode, or a wavelength preset (as a string) for a discrete mode.

**get\_range\_info()**

Get power range info.

Return tuple (*curr\_idx*, *ranges*, *curr\_range*), where *curr\_idx* is the current power range index, *ranges* is the list of ranges (in W) for all indices and *curr\_range* is the current range (in W).

**get\_range()**

Get current power range (maximal power in W)

**get\_range\_idx()**

Get current power range index

Index goes from 0 (highest) to maximal (lowest); auto-ranging is -1.

**set\_range\_idx(*rng\_idx*)**

Set current range index.

*rng\_idx* is the range index from 0 (highest) to maximal (lowest); auto-ranging is -1. The corresponding ranges are given by [get\\_range\\_info\(\)](#).

**set\_range(*rng*)**

Set current power range.

Select the smallest available range which is larger than *rng* (or maximal range, if the requested range is too large) If *rng* is "auto", enable autorange; if *rng* is None, set to the maximal range.

**get\_battery\_condition()**

Check if the batter is OK

**get\_baudrate()**

Get current baud rate

**get\_supported\_baudrates()**

Get a list of all supported baud rates

**set\_baudrate(*baudrate*)**

Set current baud rate.

If the baudrate is different from the current one, close the device connection. The device object will need to be re-created with the newly specified baud rate.

**is\_filter\_in()**

Check if the filter is set to be on at the power meter

**set\_filter(*filter\_in=True*)**

Change the filter setting at the power meter (on or off)

**is\_diffuser\_in()**

Check if the diffuser is set to be on at the power meter

**set\_diffuser(*diffuser\_in=True*)**

Change the diffuser setting at the power meter (on or off)

**Error**

alias of [OphirError](#)

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(*include=0*)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(*include=0*)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**query**(*comm*)

Send a query to the device and parse the reply

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.PCO package

#### Submodules

#### pylablib.devices.PCO.SC2 module

`pylablib.devices.PCO.SC2.list_cameras`(*cam\_interface=None*)

List camera connections (interface kind and camera index).

If *cam\_interface* is supplied, it defines one of camera interfaces to check (e.g., "usb3" or "clhs"). Otherwise, check all interfaces.

`pylablib.devices.PCO.SC2.get_cameras_number`(*cam\_interface=None*)

Get the total number of connected PCOSC2 cameras.

If *cam\_interface* is supplied, it defines one of camera interfaces to check (e.g., "usb3" or "clhs"). Otherwise, check all interfaces.

`pylablib.devices.PCO.SC2.reset_api()`

Reset API.

All cameras must be closed; otherwise, the prompt to reboot will appear.

**class** `pylablib.devices.PCO.SC2.TDeviceInfo`(*model, interface, sensor, serial\_number*)

Bases: `tuple`

**interface**

**model**

**sensor**

**serial\_number**

```
class pylablib.devices.PCO.SC2.TCameraStatus(status, warnings, errors)
```

Bases: `tuple`

**errors**

**status**

**warnings**

```
class pylablib.devices.PCO.SC2.TInternalBufferStatus(scheduled, scheduled_max, overruns)
```

Bases: `tuple`

**overruns**

**scheduled**

**scheduled\_max**

```
class pylablib.devices.PCO.SC2.TFrameInfo(frame_index)
```

Bases: `tuple`

**frame\_index**

```
class pylablib.devices.PCO.SC2.PCOSC2Camera(idx=0, cam_interface=None, reboot_on_fail=True)
```

Bases: `IBinROICamera`, `IExposureCamera`

PCO SC2 camera.

#### Parameters

- **idx** (*int*) – camera index (use `get_cameras_number()` to get the total number of connected cameras)
- **cam\_interface** – camera interface; if it is `None`, get the first available connected camera (in this case *idx* is ignored); if not, then value of *idx* is used to connect to a particular camera (interfaces and indices can be obtain from `list_cameras()`)
- **reboot\_on\_fail** (*bool*) – if `True` and the camera raised an error during initialization (but after opening), reboot the camera and try to connect again useful when the camera is in a broken state (e.g., wrong ROI or pixel clock settings)

```
Error = <Mock name='mock.PCOSC2Error' id='140527595093840'>
```

```
TimeoutError = <Mock spec='str' id='140527596755152'>
```

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**reboot(wait=True)**

Reboot the camera.

If `wait==True`, wait for the recommended time (10 seconds) after reboot for the camera to fully restart; attempt to open the camera before that can lead to an error.

**get\_full\_camera\_data()**

Get a dictionary the all camera data available through the SDK

**update\_full\_data()**

Update internal full camera data settings.

Takes some time (about 50ms), so more specific function are preferable for specific parameters.

**get\_device\_info()**

Get camera model data.

Return tuple (model, interface, sensor, serial\_number).

**get\_capabilities()**

Get camera capabilities.

For description of the capabilities, see PCO SC2 manual.

**get\_camera\_status(full=False)**

Get camera status.

If `full==True`, return current camera status as a set of enabled status states; otherwise, return tuple (status, warnings, errors) with additional information about warnings and error.

**get\_temperature()**

Get the current camera temperature

Return tuple (CCD, cam, power) with temperatures of the sensor, camera, and power supply respectively.

**get\_conversion\_factor()**

Get camera conversion factor (electrons per pixel value)

**get\_trigger\_mode()**

Get current trigger mode (see [set\\_trigger\\_mode\(\)](#) for description)

**set\_trigger\_mode(mode)**

Set trigger mode.

Can be "int" (internal), "software" (software), "ext" (external+software), "ext\_exp" (external exposure), "ext\_sync" (external PLL sync), "ext\_exp\_fast" (fast external exposure), "ext\_cds" (external CDS control), "ext\_exp\_slow" (slow external exposure), or "ext\_sync\_hdsdi" (external synchronized SD/HDI).

For description, see PCO SDK manual.

**send\_software\_trigger()**

Send software trigger signal

**class ScheduleLooper**

Bases: [object](#)

Cython-based schedule loop manager.

Runs the loop function and provides callback storage.

**loop**(handle, nbuff, buffers, buffer\_size, set\_idx)

**reset**()

**notify**()



**class BufferManager**(*nbuff*, *size*, *metadata\_size*=0)

Bases: [object](#)

Frame buffer managers.

Stores and accesses frame buffer and status arrays and buffer info.

**get\_buffer\_ptr**(*n*)

Get address of n'th frame buffer

**get\_internal\_buffer\_status**()

Get the status of the internal smaller API buffer, showing the number of scheduled frames there, and the maximal number that can be scheduled

**set\_exposure**(*exposure*)

Set camera exposure

**get\_exposure**()

Get current exposure

**set\_frame\_delay**(*frame\_delay*)

Set camera frame delay

**get\_frame\_delay**()

Get current frame delay

**set\_frame\_period**(*frame\_time*=0, *adjust\_exposure*=False)

Set frame time (frame acquisition period).

If the time can't be achieved even with zero frame delay and *adjust\_exposure*==True, try to reduce the exposure to get the desired frame time; otherwise, keep the exposure the same.

**get\_frame\_period**()

Get current frame time (frame acquisition period)

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (*exposure*, *frame\_period*).

**get\_pixel\_rate**()

Get camera pixel rate (in Hz)

**get\_available\_pixel\_rates**()

Get all available pixel rates

**set\_pixel\_rate**(*rate*=None)

Set camera pixel rate (in Hz)

The rate is always rounded to the closest available. If *rate* is None, set the maximal possible rate.

**setup\_acquisition**(*nframes*=100)

Setup acquisition.

*nframes* determines number of size of the ring buffer (by default, 100).

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth:`setup\_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None).

Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition.

Clears buffers as well, so any readout afterwards is impossible.

**acquisition\_in\_progress()**

Check if the acquisition is in progress

**clear\_acquisition()**

Clear acquisition settings

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*, *hbin=1*, *vbin=1*, *symmetric=False*)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning). If *symmetric==True* and camera requires symmetric ROI (see [requires\\_symmetric\\_roi\(\)](#)), respect this symmetry in the resulting ROI; otherwise, try to use software ROI feature to set up the required ranges (note: while software ROI does affect the size of the read out frame, it does not change the readout time, which would be the same as with *symmetric==True*).

**requires\_symmetric\_roi()**

Check if the camera requires horizontally or vertically symmetric ROI.

Return a tuple (*horizontal*, *vertical*). If *True*, one might still set up an asymmetric ROI for some cameras using the software ROI feature, but it does not affect camera readout rate

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**enable\_pixel\_correction(*enable=True*)**

Enable or disable hotpixel correction

**is\_pixel\_correction\_enabled()**

Check if hotpixel correction is enabled

**get\_noise\_filter\_mode()**

Get the noise filter mode (for details, see [set\\_noise\\_filter\\_mode\(\)](#))

**set\_noise\_filter\_mode**(*mode*='on')

Set the noise filter mode.

Can be "off", "on", or "on\_hpc" (on + hot pixel correction).

**set\_status\_line\_mode**(*binary*=True, *text*=False)

Set status line mode.

*binary* determines if the binary line is present (it occupies first 14 pixels of the image). *text* determines if the text line is present (it is plane text timestamp, which takes first 8 rows and about 300 columns).

It is recommended to always have *binary* option on, since it is used to determine frame index for checking if there are any missing frames.

**get\_status\_line\_mode**()

Get status line mode.

Return tuple (*binary*, *text*) (see [`set\_status\_line\_mode\(\)`](#) for description)

**get\_bit\_alignment**()

Get data bit alignment

Can be "LSB" (normal alignment) or "MSB" (if camera data is less than 16 bit, it is padded with zeros on the right to match 16 bit).

**set\_bit\_alignment**(*mode*)

Get data bit alignment

Can be "LSB" (normal alignment) or "MSB" (if camera data is less than 16 bit, it is padded with zeros on the right to match 16 bit).

**set\_metadata\_mode**(*mode*=True)

Set metadata mode

**get\_metadata\_mode**()

Get metadata mode.

Return tuple (*enabled*, *size*, *version*)

**get\_double\_image\_mode**()

Check if the double image mode is active

**set\_double\_image\_mode**(*enable*)

Enable or disable the double image mode

**FrameTransferError**

alias of [`DefaultFrameTransferError`](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {*name*: *value*}

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(*include=0*)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(*include=0*)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.PC0.SC2.TStatusLine(framestamp)`

Bases: `tuple`

**framestamp**

`pylablib.devices.PC0.SC2.get_status_line(frame)`

Get frame info from the binary status line.

Assume that the status line is present; if it isn't, the returned frame info will be a random noise.

`pylablib.devices.PC0.SC2.get_status_lines(frames)`

Get frame info from the binary status line.

*frames* can be 2D array (one frame), 3D array (stack of frames, first index is frame number), or list of 1D or 2D arrays. Assume that the status line is present; if it isn't, the returned frame info will be a random noise. Return a 1D or 2D numpy array, where the first axis (if present) is the frame number, and the last is the status line entry.

**class** `pylablib.devices.PC0.SC2.StatusLineChecker`

Bases: `StatusLineChecker`

**get\_framestamp(*frames*)**

Get framestamps from status lines in the given frames

**check\_indices(*indices*, *step=1*)**

Check if indices are consistent with the given step

## Module contents

### `pylablib.devices.Pfeiffer` package

#### Submodules

#### `pylablib.devices.Pfeiffer.base` module

**exception** `pylablib.devices.Pfeiffer.base.PfeifferError`

Bases: `DeviceError`

Generic Pfeiffer device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Pfeiffer.base.PfeifferBackendError`(*exc*)

Bases: `PfeifferError`, `DeviceBackendError`

Generic Pfeiffer backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.devices.Pfeiffer.base.TTPG260SwitchSettings`(*channel*, *low\_thresh*, *high\_thresh*)

Bases: `tuple`

**channel**

**high\_thresh**

**low\_thresh**

**class** `pylablib.devices.Pfeiffer.base.TTPG260GaugeControlSettings`(*activation\_control*,  
*deactivation\_control*,  
*on\_thresh*, *off\_thresh*)

Bases: `tuple`

**activation\_control**

**deactivation\_control**

**off\_thresh**

**on\_thresh**

**class** `pylablib.devices.Pfeiffer.base.TPG260`(*conn*)

Bases: `ICommBackendWrapper`

TPG260 series (TPG261/262) pressure gauge.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of `PfeifferError`

**comm**(*msg*)

Send a command to the device

**query**(*msg*, *data\_type*='str')

Send a query to the device and return the reply

**get\_units**()

Get device units for indication/reading ("mbar", "torr", or "pa")

**set\_units**(*units*)

Set device units for indication/reading ("mbar", "torr", or "pa")



**to\_Pa**(*value*, *units=None*)

Convert value in the given units to Pa.

If *units* is *None*, use the current display units.

**from\_Pa**(*value*, *units=None*)

Convert value in the given units from Pa.

If *units* is *None*, use the current display units.

**get\_display\_channel**()

Get controller display channel

**set\_display\_channel**(*channel=1*)

Set controller display channel

**get\_display\_resolution**()

Get controller display resolution (number of digits)

**set\_display\_resolution**(*resolution=2*)

Set controller display resolution (number of digits)

**is\_enabled**(*channel=1*)

Check if the gauge at the given channel is enabled.

If the gauge cannot be turned on/off (e.g., not connected), return *None*.

**enable**(*enable=True*, *channel=1*)

Enable or disable the gauge at the given channel

**get\_channel\_status**(*channel=1*)

Get channel status.

Can be "ok", "under" (underrange), "over" (overrange), "sensor\_error", "sensor\_off", "no\_sensor", or "id\_error".

**get\_pressure**(*channel=1*, *display\_units=False*, *status\_error=True*)

Get pressure at a given channel.

If *display\_units==False*, return result in Pa; otherwise, use display units obtained using [get\\_units\(\)](#). If *status\_error==True* and the channel status is not "ok", raise an error; otherwise, return *None*.

**get\_gauge\_kind**(*channel=1*)

**get\_measurement\_filter**(*channel=1*)

Get gauge measurement filter ("fast", "medium", or "slow")

**set\_measurement\_filter**(*meas\_filter*, *channel=1*)

Set gauge measurement filter ("fast", "medium", or "slow")

**get\_calibration\_factor**(*channel=1*)

Get gauge calibration factor

**set\_calibration\_factor**(*coefficient*, *channel=1*)

Set gauge calibration factor

**get\_switch\_settings**(*switch\_function*)

Get settings for the given switch function (between 1 and 4).

Return tuple (*channel*, *low\_thresh*, *high\_thresh*). The thresholds are given in Pa.

**setup\_switch**(*switch\_function*, *channel*, *low\_thresh*, *high\_thresh*)

Get settings for the given switch function (between 1 and 4).

Return tuple (*channel*, *low\_thresh*, *high\_thresh*). The thresholds are given in Pa.

**get\_switch\_status**()

Return status of the 4 switch functions

**get\_gauge\_control\_settings**(*channel*)

Get settings for the gauge control on the given channel.

Return tuple (*activation\_control*, *deactivation\_control*, *on\_thresh*, *off\_thresh*). The thresholds are given in Pa.

**setup\_gauge\_control**(*channel*, *activation\_control*, *deactivation\_control*, *on\_thresh*, *off\_thresh*)

Setup gauge control on the given channel.

Return tuple (*activation\_control*, *deactivation\_control*, *on\_thresh*, *off\_thresh*). The thresholds are given in Pa.

**get\_current\_errors**()

Get a list of all present error messages.

If there are no errors, return a single-element list ["no\_error"].

**reset\_error**()

Cancel currently active errors and return to measurement mode.

Return the list of currently present errors. If there are no errors, return a single-element list ["no\_error"].

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** `pylablib.devices.Pfeiffer.base.DPG202`(*conn*)

Bases: *ICommBackendWrapper*

DPG202/TPG202 control unit.

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**Error**

alias of *PfeifferError*

**query**(*parameter, value='=?', action=0, address=1, send\_type=None, recv\_type=None*)

Send a query to the device and parse the reply.

**Parameters**

- **parameter** – parameter number
- **value** – value to send ("=?" for a value request)
- **action** – request action (0 for value request, 1 for a command)
- **address** – unit address
- **send\_type** – data type for the sent value (ignored for value requests)
- **recv\_type** – data type for the received value (None means returning a raw string value)

**get\_value**(*parameter, data\_type, address=1*)

Send a data request to the device.

**Parameters**

- **parameter** – parameter number
- **data\_type** – data type for the received value
- **address** – unit address

**comm**(*parameter, value, data\_type, address=1*)

Send a control command to the device.

**Parameters**

- **parameter** – parameter number

- **value** – associated command value
- **data\_type** – data type for the sent value
- **address** – unit address

**get\_pressure**(*address=1*)

Get pressure at a given unit address

**get\_error\_code**(*address=1*)

Get the current error code at a given unit address

**get\_software\_version**(*address=1*)

Get the software version at a given unit address

**get\_device\_name**(*address=1*)

Get the name of the gauge at a given unit address

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {**name**: **value**} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {**name**: **value**} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**get\_full\_status**(*include=0*)

Get dict {**name**: **value**} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**get\_settings**(*include=0*)

Get dict {**name**: **value**} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Photometrics package

#### Submodules

#### pylablib.devices.Photometrics.pvcam module

**class** pylablib.devices.Photometrics.pvcam.**LibraryController**(*lib*)

Bases: *LibraryController*

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

pylablib.devices.Photometrics.pvcam.**list\_cameras**()

List all cameras available through Pvcam interface

pylablib.devices.Photometrics.pvcam.**get\_cameras\_number**()

Get number of connected Pvcam cameras

**class** pylablib.devices.Photometrics.pvcam.**PvcamAttribute**(*handle, pid, cam=None*)

Bases: *object*

Object representing an Pvcam camera parameter.

Allows to query and set values and get additional information. Usually created automatically by an *PvcamCamera* instance, but could be created manually.

**Parameters**

- **handle** – camera handle
- **pid** – parameter id of the attribute

**name**

attribute name

**kind**

attribute kind; can be "INT8", "INT16", "INT32", "INT64", "UNS8", "UNS16", "UNS32", "UNS64", "FLT32", "FLT64", "ENUM", "BOOLEAN", or "CHAR\_PTR"

**available**

whether attribute is available on the current hardware

**Type**

bool

**readable**

whether attribute is readable

**Type**

bool

**writable**

whether attribute is writable

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**inc**

minimal attribute increment value (if applicable)

**Type**

float or int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**default**

default values of the attribute

**update\_limits()**

Update attribute constraints

**truncate\_value(value)**

Truncate value to lie within attribute limits

**get\_value(enum\_as\_str=True, error\_on\_noacq=True)**

Get attribute value.

If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_value(value, truncate=True)**

Set attribute value.

If `truncate==True`, automatically truncate value to lie within allowed range.

**class** pylablib.devices.Photometrics.pvcam.**TDeviceInfo**(*vendor, product, chip, system, part, serial*)

Bases: `tuple`

**chip**

**part**

**product**

**serial**

**system**

**vendor**

**class** pylablib.devices.Photometrics.pvcam.**TFrameInfo**(*frame\_index, timestamp\_start\_ns, timestamp\_end\_ns, framestamp, flags, exposure\_ns*)

Bases: `tuple`

**exposure\_ns**

**flags**

**frame\_index**

**framestamp**

**timestamp\_end\_ns**

**timestamp\_start\_ns**

**class** pylablib.devices.Photometrics.pvcam.**TReadoutInfo**(*port\_idx, port\_name, speed\_idx, speed\_freq, gain\_idx, gain\_name*)

Bases: `tuple`

`gain_idx`  
`gain_name`  
`port_idx`  
`port_name`  
`speed_freq`  
`speed_idx`

**class** `pylablib.devices.Photometrics.pvcam.PvcamCamera`(*name=None*)

Bases: `IBinROICamera`, `IExposureCamera`, `IAttributeCamera`

Generic Pvcam camera interface.

**Parameters**

**serial\_number** – camera serial number; if None, connect to the first non-used camera

**Error** = `<Mock name='mock.PvcamError' id='140527603414160'>`

**TimeoutError** = `<Mock spec='str' id='140527600166608'>`

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_attribute\_value**(*name*, *error\_on\_missing=True*, *error\_on\_noacq=False*, *default=None*,  
*enum\_as\_str=True*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not None, assume that `error_on_missing==False`. If *name* points at a dictionary branch, return a dictionary with all values in this branch. If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_attribute\_value**(*name*, *value*, *truncate=True*, *error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If `truncate==True`, truncate value to lie within attribute range.

**get\_all\_attribute\_values**(*root=""*, *enum\_as\_str=True*, *error\_on\_noacq=False*)

Get values of all attributes with the given *root*

**set\_all\_attribute\_values**(*settings*, *root=""*, *truncate=True*)

Set values of all attributes with the given *root*.

If `truncate==True`, truncate value to lie within attribute range.



**get\_attribute\_range**(*name*, *error\_on\_missing=True*, *default=None*, *parameter=None*)

Return attribute range.

For numerical attributes it is a tuple (min, max), while for enum attributes it is a dictionary {index: name}. If *parameter* is specified, it is a parameter class used to convert the index for a enum attribute.

**get\_all\_readout\_modes**()

Get a list of all possible readout modes.

Return a list of tuples (port\_idx, port\_name, speed\_idx, speed\_freq, gain\_idx, gain\_name). The indices (port, speed, and gain) can be used to set up a particular mode using [set\\_readout\\_mode\(\)](#).

**get\_readout\_mode**(*full=True*)

Get current readout mode.

If *full==True*, return a full tuple (port\_idx, port\_name, speed\_idx, speed\_freq, gain\_idx, gain\_name) containing the descriptions; otherwise, return only indices (port\_idx, speed\_idx, gain\_idx).

**set\_readout\_mode**(*port\_idx=None*, *speed\_idx=None*, *gain\_idx=None*)

Set the readout mode.

Any None value stays unchanged.

**get\_device\_info**()

Get camera information.

Return tuple (vendor, product, chip, system, part, serial).

**get\_pixel\_size**()

Get camera pixel size (in m)

**get\_pixel\_distance**()

Get camera pixel distance (in m)

**get\_temperature\_setpoint**()

Get the temperature setpoint (in C)

**get\_temperature**()

Get the current camera temperature (in C)

**set\_temperature**(*temp*)

Change the temperature setpoint (in C)

**get\_fan\_mode**()

Get current fan mode

**set\_fan\_mode**(*fan\_mode='high'*)

Set current fan mode

**is\_metadata\_enabled**()

Check if metadata is enabled

**enable\_metadata**(*enable=True*)

Enable or disable metadata

**get\_exposure**()

Get current exposure

**set\_exposure**(*exposure*)

Set camera exposure

**get\_clear\_mode**()

Get sensor clear mode

**set\_clear\_mode**(*mode*)

Set sensor clear mode

**get\_clear\_cycles**()

Get sensor clear cycles

**set\_clear\_cycles**(*ncycles*)

Set sensor clear cycles

**get\_clearing\_time**()

Get sensor clearing time (regardless of the mode)

**get\_readout\_time**(*include\_clear=True*)

Get frame readout time.

If *include\_clear==True* and the clear mode is per-exposure ("Pre-Exposure" or "Pre-Exposure and Post-Sequence"), include it into this time.

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (*exposure*, *frame\_period*).

**get\_trigger\_mode**()

Get trigger mode

**set\_trigger\_mode**(*mode*, *out\_mode=None*)

Set trigger mode

**send\_software\_trigger**()

Send software trigger signal and return whether it has been accepted

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_roi**()

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*, *hbin=1*, *vbin=1*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits**(*hbin=1*, *vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_supported\_binning\_modes()**

Get all possible binning combinations as a list [(hbin, vbin)]

**setup\_acquisition(mode='sequence', nframes=100)**

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frame buffers.

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek*==True, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==True, return tuple (*frames*, *infos*), where *infos* is a list of *TFrameInfo* instances describing frame index and frame metadata, which contains start and stop timestamps, framestamp, frame flags, and exposure; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is None. if *return\_rng*==True, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attributes(copy=False)**

Return a dictionary of all available attributes.

If *copy*==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute**(*name*, *error\_on\_missing=True*)

Get the camera attribute with the given name

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields**()

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format**()

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period**()

Get period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period**()

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frames\_status**()

Get acquisition and buffer status.

Return tuple (*acquired*, *unread*, *skipped*, *size*), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_newest\_image(peek=False, return\_info=False)**

Read the newest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (frame, info), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

`pylablib.devices.Photometrics.pvcam.get_roi_parameters(buffer)`

Extract ROI parameters from the buffer.

*buffer* is the buffer represented as bytes numpy byte array. Return numpy array with one row per ROI and 4 columns: data offset from the frame start, data bytes per pixel, ROI height, and ROI width.

`pylablib.devices.Photometrics.pvcam.parse_metainfo_v1(buffer, nframes, stride)`

Extract frames metainfo for frames with v1 or v2 header.

*buffer* is the buffer represented as bytes numpy byte array, *nframes* is the number of frames in it, and *stride* is the frame stride (in bytes).

Return a 2D array with *nframes* rows and 7 columns: `framestamp`, `timestampBOF`, `timestampEOF`, `timestampRes`, `exposure`, `exposureRes`, `flags`.

`pylablib.devices.Photometrics.pvcam.parse_metainfo_v3(buffer, nframes, stride)`

Extract frames metainfo for frames with v3 header.

*buffer* is the buffer represented as bytes numpy byte array, *nframes* is the number of frames in it, and *stride* is the frame stride (in bytes).

Return a 2D array with *nframes* rows and 5 columns: `framestamp`, `timestampBOF`, `timestampEOF`, `exposure`, `flags`.

## Module contents

### `pylablib.devices.PhotonFocus` package

#### Submodules

### `pylablib.devices.PhotonFocus.PhotonFocus` module

`class pylablib.devices.PhotonFocus.PhotonFocus.LibraryController(lib)`

Bases: `LibraryController`

`close(opid)`

Mark device closing.

Return tuple (`close_result`, `uninit_result`) with the results of the closing and the shutdown. If library does not need to be shut down yet, set `uninit_result=None`

`get_opened_num()`

Get number of opened devices

`open()`

Mark device opening.

Return tuple (`init_result`, `open_result`, `opid`) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set `init_result=None`

`preinit()`

Pre-initialize the library, if it hasn't been done already

`shutdown()`

Close all opened connections and shutdown the library

**temp\_open()**

Context for temporarily opening a new device connection

`pylablib.devices.PhotonFocus.PhotonFocus.query_camera_name(port)`

Query cameras name at a given port in PFCam interface

**class** `pylablib.devices.PhotonFocus.PhotonFocus.TCameraInfo`(*manufacturer, port, version, type*)

Bases: `tuple`

**manufacturer**

**port**

**type**

**version**

`pylablib.devices.PhotonFocus.PhotonFocus.list_cameras`(*only\_supported=True*)

List all cameras available through PFCam interface.

If `only_supported==True`, only return cameras which support PFCam protocol (this check only works if the camera is not currently accessed by some other software). Return a list [(`port`, `info`)], where `port` is the pfcam port given to [IPhotonFocusCamera](#) and its subclasses, and `info` is the information returned by [query\\_camera\\_name\(\)](#).

`pylablib.devices.PhotonFocus.PhotonFocus.get_cameras_number`(*only\_supported=True*)

Get the total number of connected PFCam cameras

`pylablib.devices.PhotonFocus.PhotonFocus.get_port_index`(*manufacturer, port*)

Find PhotonFocus port index based on the manufacturer and port

**class** `pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute`(*port, name*)

Bases: `object`

PFCam camera attribute.

Allows to query and set values and get additional information. Usually created automatically by a PhotonFocus camera instance, but could also be created manually.

#### Parameters

- **sid** – camera session ID
- **name** – attribute text name

**name**

attribute name

**kind**

attribute kind; can be "INT", "UINT", "FLOAT", "BOOL", "MODE", "STRING", or "COMMAND"

**readable**

whether attribute is readable

**Type**

`bool`

**writable**

whether attribute is writable

**Type**

`bool`



**is\_command**

whether attribute is a command

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**update\_limits()**

Update minimal and maximal attribute limits and return tuple (min, max)

**truncate\_value(value)**

Truncate value to lie within attribute limits

**get\_value(enum\_as\_str=True)**

Get attribute value.

If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_value(value, truncate=True)**

Get attribute value.

If `truncate==True`, automatically truncate value to lie within allowed range.

**call\_command(arg=0)**

If attribute is a command, call it with a given argument; otherwise, raise an error

**class** pylablib.devices.PhotonFocus.PhotonFocus.**TDeviceInfo**(*model, serial\_number, grabber\_info*)

Bases: tuple

**grabber\_info****model****serial\_number**

**class** `pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera`(*pfcam\_port=0, \*\*kwargs*)

Bases: [`IAttributeCamera`](#)

Generic PFCam interface to a PhotonFocus camera. Does not handle frames acquisition, so needs to be mixed with a frame grabber class to be fully operational. In this mixing, the class attribute `GrabberClass` should be set to this frame grabber class.

#### Parameters

- **pfcam\_port** – port number for pfcam interface (can be learned by [`list\_cameras\(\)`](#); port number is the first element of the camera data tuple) can also be a tuple (manufacturer, port), e.g., ("National Instruments", "port0").
- **kwargs** – keyword arguments passed to the frame grabber initialization

#### Error

alias of [`DeviceError`](#)

**GrabberClass** = `None`

**setup\_max\_baudrate()**

Setup the maximal available baudrate

**get\_baudrate()**

Get the current baud rate

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**get\_attribute\_value**(*name, enum\_as\_str=True, error\_on\_missing=True, default=None*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not `None`, assume that `error_on_missing==False`. If `enum_as_str==True`, try to represent enums as their string values; If *name* points at a dictionary branch, return a dictionary with all values in this branch.

**set\_attribute\_value**(*name, value, truncate=True, error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If `truncate==True`, truncate value to lie within attribute range.

**get\_all\_attribute\_values**(*root="", enum\_as\_str=True*)

Get values of all attributes with the given *root*

**set\_all\_attribute\_values**(*settings, root="", truncate=True*)

Set values of all attributes with the given *root*.

If `truncate==True`, truncate value to lie within attribute range.

**update\_attribute\_value**(*name, value, error\_on\_missing=True, truncate=True*)

Set value of the attribute with a given name, but only if it's different from the current value.

Can take less time on some version of PFRremote (where single attribute setting is about 50ms). Arguments are the same as [`set\_attribute\_value\(\)`](#).

**call\_command**(*name*, *arg*=0, *error\_on\_missing*=True)

Execute the given command with the given argument.

If the command doesn't exist and *error\_on\_missing*==True, raise error; otherwise, do nothing.

**get\_device\_info**()

Get camera model data.

Return tuple (model, serial\_number, grabber\_info).

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi**()

Get current ROI.

Return tuple (hstart, hend, vstart, vend).

**fast\_shift\_roi**(*hstart*=0, *vstart*=0)

Shift ROI by only changing its origin, but keeping the shape the same.

Note that if the ROI is invalid, it won't be truncated (as is the standard behavior of [set\\_roi\(\)](#)), which might lead to errors later.

**set\_roi**(*hstart*=0, *hend*=None, *vstart*=0, *vend*=None)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**get\_roi\_limits**(*hbin*=1, *vbin*=1)

**get\_exposure**()

Get current exposure

**set\_exposure**(*exposure*)

Set current exposure

**get\_frame\_period**()

Get frame period (time between two consecutive frames in the internal trigger mode)

**set\_frame\_period**(*frame\_period*)

Set frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (exposure, frame\_period).

**is\_CFR\_enabled**()

Check if the constant frame rate mode is enabled

**enable\_CFR**(*enabled*=True)

Enable constant frame rate mode

**get\_trigger\_interleave**()

Check if the trigger interleave is on

**set\_trigger\_interleave**(*enabled*)

Set the trigger interleave option on or off

**is\_status\_line\_enabled()**

Check if the status line is on

**enable\_status\_line(*enabled=True*)**

Enable or disable status line

**get\_black\_level\_offset()**

Get the black level offset

**set\_black\_level\_offset(*offset*)**

Set the black level offset

**FrameTransferError**

alias of *DefaultFrameTransferError*

**TimeoutError**

alias of *DeviceError*

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(*settings*)**

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {*name*: *value*}

**get\_all\_attributes(*copy=False*)**

Return a dictionary of all available attributes.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute(*name*, *error\_on\_missing=True*)**

Get the camera attribute with the given name

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**is\_opened**()

Check if the device is connected

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(key, value)

Set the value of a settings parameter

**set\_frame\_format**(fmt)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(fmt, include\_fields=None)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(period=1)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(indexing)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition**(\*\*kwargs)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap**(timeout=5.0, return\_info=False)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth:`setup\_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is `None`). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera`(*imaq\_name='img0', pfcam\_port=0*)

Bases: [IPhotonFocusCamera](#), [IMAQFrameGrabber](#)

IMAQ+PFCam interface to a PhotonFocus camera.

#### Parameters

- **imaq\_name** – IMAQ interface name (can be learned by [IMAQ.list\\_cameras\(\)](#); usually, but not always, starts with "img")
- **pfcam\_port** – port number for pfcam interface (can be learned by [list\\_cameras\(\)](#); port number is the first element of the camera data tuple) can also be a tuple (manufacturer, port), e.g., ("National Instruments", "port0").

#### Error

alias of [DeviceError](#)

#### GrabberClass

alias of [IMAQFrameGrabber](#)

**open()**

Open connection to the camera

#### FrameTransferError

alias of [DefaultFrameTransferError](#)

**TimeoutError** = <Mock spec='str' id='140527693277200'>

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**call\_command**(*name, arg=0, error\_on\_missing=True*)

Execute the given command with the given argument.

If the command doesn't exist and *error\_on\_missing*==True, raise error; otherwise, do nothing.

**clear\_acquisition()**

Clear all acquisition details and free all buffers



**clear\_all\_triggers**(*reset\_acquisition=True*)

Disable all triggers of the session

If the input triggers configuration has been changed, acquisition needs to be restart; if `reset_acquisition==True`, perform it automatically.

**close**()

Close connection to the camera

**configure\_trigger\_in**(*trig\_type*, *trig\_line=0*, *trig\_pol='high'*, *trig\_action='none'*, *timeout=None*, *reset\_acquisition=True*)

Configure input trigger.

#### Parameters

- **trig\_type** (*str*) – trigger source type; can be "ext", "rtsi", "iso\_in", or "software"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_action** (*str*) – trigger action; can be "none" (disable trigger), "capture" (start capturing), "stop" (stop capturing), "buffer" (capture a single frame), or "bufflist" (capture the whole buffer list once)
- **timeout** (*float*) – timeout in seconds; `None` means not timeout.
- **reset\_acquisition** (*bool*) – if the input triggers configuration has been changed, acquisition needs to be restart; if `True`, perform it automatically

**configure\_trigger\_out**(*trig\_type*, *trig\_line=0*, *trig\_pol='high'*, *trig\_drive='disable'*)

Configure trigger output.

#### Parameters

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"
- **trig\_drive** (*str*) – trigger output signal; can be "disable" (disable drive), "acq\_in\_progress" (asserted when acquisition is started), "acq\_done" (asserted when acquisition is done), "unasserted" (force unasserted level), "asserted" (force asserted level), "hsync" (asserted on start of a single line start), "vsync" (asserted on start of a frame scan), "frame\_start" (asserted when a single frame is captured), or "frame\_done" (asserted when a single frame is done)

**enable\_CFR**(*enabled=True*)

Enable constant frame rate mode

**enable\_status\_line**(*enabled=True*)

Enable or disable status line

**fast\_shift\_roi**(*hstart=0*, *vstart=0*)

Shift ROI by only changing its origin, but keeping the shape the same.

Note that if the ROI is invalid, it won't be truncated (as is the standard behavior of `set_roi()`), which might lead to errors later.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attribute\_values**(root="", enum\_as\_str=True)

Get values of all attributes with the given *root*

**get\_all\_attributes**(copy=False)

Return a dictionary of all available attributes.

If *copy*==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_all\_grabber\_attribute\_values()**

Get a dictionary of all readable attributes.

The attributes types are autodetected, and some of the types of uncommon attributes may be misrepresented.

**get\_attribute**(name, error\_on\_missing=True)

Get the camera attribute with the given name

**get\_attribute\_value**(name, enum\_as\_str=True, error\_on\_missing=True, default=None)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and *error\_on\_missing*==True, raise error; otherwise, return *default*. If *default* is not None, assume that *error\_on\_missing*==False. If *enum\_as\_str*==True, try to represent enums as their string values; If *name* points at a dictionary branch, return a dictionary with all values in this branch.

**get\_baudrate()**

Get the current baud rate

**get\_black\_level\_offset()**

Get the black level offset

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info()**

Get camera model data.

Return tuple (model, serial\_number, grabber\_info).

**get\_device\_variable**(key)

Get the value of a settings, status, or full info parameter

**get\_exposure()**

Get current exposure

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (exposure, frame\_period).

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_grabber\_attribute\_value(attr, default=None, kind='auto')**

Get value of an attribute with a given name or index.

If *default* is not None, return *default* if the attribute is not supported; otherwise, raise an error. *kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*).

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_serial\_params()**

Return serial parameters as a tuple (*write\_term*, *datatype*)

**get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_interleave()**

Check if the trigger interleave is on

**grab(*nframes=1*, *frame\_timeout=5.0*, *missing\_frame='skip'*, *return\_info=False*, *buff\_size=None*)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*,

return tuple (frames, infos), where infos is a list of frame info tuples (camera-dependent); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is None.

**is\_CFR\_enabled()**

Check if the constant frame rate mode is enabled

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**is\_status\_line\_enabled()**

Check if the status line is on

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (None means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (None means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If `peek==True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (frames, infos), where infos is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is None. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return None. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_trigger**(*trig\_type*, *trig\_line*=0, *trig\_pol*='high')

Read current value of a trigger (input or output).

**Parameters**

- **trig\_type** (*str*) – trigger drive destination type; can be "ext", "rtsi", "iso\_in", or "iso\_out"
- **trig\_line** (*int*) – trigger line number
- **trig\_pol** (*str*) – trigger polarity; can be "high" or "low"

**reset**()

Reset connection to the camera

**send\_software\_trigger**()

Send software trigger signal

**serial\_flush**()

Flush CameraLink serial port

**serial\_read**(*n*, *timeout*=3.0, *datatype*=None)

Read specified number of bytes from CameraLink serial port.

**Parameters**

- **n** – number of bytes to read
- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if `None`, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")

**serial\_readline**(*timeout*=3.0, *datatype*=None, *maxn*=1024)

Read bytes from CameraLink serial port until the termination character (defined in camera file) is encountered.

**Parameters**

- **timeout** – operation timeout (in seconds)
- **datatype** – return datatype; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string) if `None`, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, "bytes")
- **maxn** – maximal number of bytes to read

**serial\_write**(*msg*, *timeout*=3.0, *term*=None)

Write message into CameraLink serial port.

**Parameters**

- **timeout** – operation timeout (in seconds)
- **term** – additional write terminator character to add to the message; if `None`, use the value set up using [setup\\_serial\\_params\(\)](#) (by default, no additional terminator)

**set\_all\_attribute\_values**(*settings*, *root*="", *truncate*=True)

Set values of all attributes with the given *root*.

If *truncate*==True, truncate value to lie within attribute range.

**set\_attribute\_value**(*name*, *value*, *truncate*=True, *error\_on\_missing*=True)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and *error\_on\_missing*==True, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If *truncate*==True, truncate value to lie within attribute range.

**set\_black\_level\_offset**(*offset*)

Set the black level offset

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_exposure**(*exposure*)

Set current exposure

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt*, *include\_fields*=None)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period*=1)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_frame\_period**(*frame\_period*)

Set frame period (time between two consecutive frames in the internal trigger mode)

**set\_grabber\_attribute\_value**(*attr*, *value*, *kind*='int32')

Set value of an attribute with a given name or index.

*kind* is the attribute kind, and it can be "uint32", "uint64", "double", or "auto" (autodetect based on the stored list of attribute kinds).

**set\_grabber\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**set\_trigger\_interleave**(*enabled*)

Set the trigger interleave option on or off

**setup\_acquisition**(*mode='sequence', nframes=100*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that `IMAQCamera.acquisition_in_progress()` would still return True in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**setup\_max\_baudrate**()

Setup the maximal available baudrate

**setup\_serial\_params**(*write\_term="", datatype='bytes'*)

Setup default serial communication parameters.

#### Parameters

- **write\_term** – default terminator character to be added to the sent messages
- **datatype** – type of the result of read commands; can be "bytes" (return raw bytes), or "str" (convert into UTF-8 string)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as `:meth:`setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**update\_attribute\_value**(*name, value, error\_on\_missing=True, truncate=True*)

Set value of the attribute with a given name, but only if it's different from the current value.

Can take less time on some version of PFRemote (where single attribute setting is about 50ms). Arguments are the same as `set_attribute_value()`.



**wait\_for\_frame**(since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (timeout, frame\_timeout), in which case the call times out if the total time exceeds timeout, or a single frame wait exceeds frame\_timeout. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

```
class pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera(siso_board,
                                                                    siso_applet=None,
                                                                    siso_port=0,
                                                                    pfcam_port=0)
```

Bases: `IPhotonFocusCamera`, `SiliconSoftwareFrameGrabber`

IMAQ+PFCam interface to a PhotonFocus camera.

#### Parameters

- **siso\_board** – Silicon Software board index, starting from 0; available boards can be learned by `fgrab.list_boards()`
- **siso\_applet** – Silicon Software applet name, which can be learned by `fgrab.list_applets()`; usually, a simple applet like "DualLineGray16" or "MediumLineGray16" are most appropriate; can be either an applet name, or a direct path to the applet DLL
- **siso\_port** – Silicon Software port number, if several ports are supported by the camera and the applet
- **pfcam\_port** – port number for pfcam interface (can be learned by `list_cameras()`; port number is the first element of the camera data tuple) can also be a tuple (manufacturer, port), e.g., ("National Instruments", "port0").

#### Error

alias of `DeviceError`

#### GrabberClass

alias of `SiliconSoftwareFrameGrabber`

#### open()

Open connection to the camera

**class BufferManager**(fg, siso\_port)

Bases: `object`

Frame buffer manager which controls and schedules the buffer and the buffer copying loop

**allocate**(nframes, frame\_size)

Allocate and schedule buffers with the given number and size

**deallocate**()

Deallocate and remove the buffers

**get\_frames\_data**(idx, nframes=1)

Get buffer chunk addresses for the given number of frames starting from the given index

**get\_status()**

Get acquisition status.

Return tuple (nread, oldest\_valid\_buffer, nacq, debug\_info)

**start\_loop(run\_nframes)**

Start the copying loop and, optionally, run the acquisition loop with the given number of frames

**stop\_loop()**

Stop the copying loop

**FrameTransferError**

alias of *DefaultFrameTransferError*

**TimeoutError** = <Mock spec='str' id='140527586806736'>

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**call\_command(name, arg=0, error\_on\_missing=True)**

Execute the given command with the given argument.

If the command doesn't exist and *error\_on\_missing*==True, raise error; otherwise, do nothing.

**clear\_acquisition()**

Clear all acquisition details and free all buffers

**close()**

Close connection to the camera

**enable\_CFR(enabled=True)**

Enable constant frame rate mode

**enable\_status\_line(enabled=True)**

Enable or disable status line

**fast\_shift\_roi(hstart=0, vstart=0)**

Shift ROI by only changing its origin, but keeping the shape the same.

Note that if the ROI is invalid, it won't be truncated (as is the standard behavior of *set\_roi()*), which might lead to errors later.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attribute\_values(root="", enum\_as\_str=True)**

Get values of all attributes with the given *root*

**get\_all\_attributes(copy=False)**

Return a dictionary of all available attributes.

If *copy*==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_all\_grabber\_attribute\_values**(*root*="", *\*\*kwargs*)

Get values of all frame grabber attributes with the given *root*.

Additional arguments are passed to `get_value` methods of individual attributes.

**get\_all\_grabber\_attributes**(*copy=False*)

Return a dictionary of all available frame grabber `grabber_attributes`.

If `copy==True`, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute**(*name*, *error\_on\_missing=True*)

Get the camera attribute with the given name

**get\_attribute\_value**(*name*, *enum\_as\_str=True*, *error\_on\_missing=True*, *default=None*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not `None`, assume that `error_on_missing==False`. If `enum_as_str==True`, try to represent enums as their string values; If *name* points at a dictionary branch, return a dictionary with all values in this branch.

**get\_available\_camlink\_pixel\_formats**()

Get all available CamLink pixel formats and the output pixel formats as a tuple of 2 lists

**get\_baudrate**()

Get the current baud rate

**get\_black\_level\_offset**()

Get the black level offset

**get\_camlink\_pixel\_format**()

Get CamLink pixel format and the output pixel format as a tuple

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (*width*, *height*); take indexing mode into account

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_device\_info**()

Get camera model data.

Return tuple (*model*, *serial\_number*, *grabber\_info*).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_exposure**()

Get current exposure

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (`exposure`, `frame_period`).

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_genicam\_info\_xml()**

Get description in Genicam-compatible XML format

**get\_grabber\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_grabber\_attribute\_value**(*name*, *error\_on\_missing=True*, *default=None*, *\*\*kwargs*)

Get value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not *None*, automatically assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. Additional arguments are passed to *get\_value* methods of the individual attribute.

**get\_grabber\_detector\_size**()

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_roi**()

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits**(*hbin=1*, *vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing**()

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range**()

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi**()

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*).

**get\_roi\_limits**(*hbin=1*, *vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_system\_info**()

Get the dictionary with all system information parameters

**get\_trigger\_interleave()**

Check if the trigger interleave is on

**grab(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where infos is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_CFR\_enabled()**

Check if the constant frame rate mode is enabled

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**is\_opened()**

Check if the device is connected

**is\_status\_line\_enabled()**

Check if the status line is on

**pausing\_acquisition(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (frames, infos), where infos is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_all\_attribute\_values**(*settings, root="", truncate=True*)

Set values of all attributes with the given *root*.

If `truncate==True`, truncate value to lie within attribute range.

**set\_all\_grabber\_attribute\_values**(*settings, root="", \*\*kwargs*)

Set values of all frame grabber attributes with the given *root*.

Additional arguments are passed to `set_value` methods of individual attributes.

**set\_attribute\_value**(*name, value, truncate=True, error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If `truncate==True`, truncate value to lie within attribute range.

**set\_black\_level\_offset**(*offset*)

Set the black level offset

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_exposure**(*exposure*)

Set current exposure

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_frame\_merge**(*frame\_merge=1*)

**set\_frame\_period**(*frame\_period*)

Set frame period (time between two consecutive frames in the internal trigger mode)

**set\_grabber\_attribute\_value**(*name, value, error\_on\_missing=True, \*\*kwargs*)

Set value of a frame grabber attribute with the given name.

If the value doesn't exist and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). Additional arguments are passed to `set_value` methods of the individual attribute.

**set\_grabber\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**set\_trigger\_interleave**(*enabled*)

Set the trigger interleave option on or off

**setup\_acquisition**(*mode='sequence', nframes=100*)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that `IMAQCamera.acquisition_in_progress()` would still return `True` in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**setup\_camlink\_pixel\_format**(*bits\_per\_pixel=8, taps=1, output\_fmt=None, fmt=None, bit\_alignment='right\_custom'*)

Set up CameraLink pixel format.

If *fmt* is `None`, use supplied *bits\_per\_pixel* (8, 10, 12, 14, or 16) and *taps* (1 or 2) to figure out the format; otherwise, *fmt* should be a numerical (e.g., 210) or string (e.g., "FG\_CL\_MEDIUM\_10\_BIT") format. *output\_fmt* specifies the result frame format; if `None`, use grayscale with the given *bits\_per\_pixel* if *fmt* is `None`, or 16 bit grayscale otherwise. *bit\_alignment* can specify the alignment of the resulting data (applicable when *bits\_per\_pixel* is not divisible by 8); can be "left", "right", "right\_custom" (explicitly calculate and set the number of bits to shift by whenever possible; this solves some issues on ME5 cards), or an integer specifying the number of bits to shift.



**setup\_max\_baudrate()**

Setup the maximal available baudrate

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**update\_attribute\_value**(*name, value, error\_on\_missing=True, truncate=True*)

Set value of the attribute with a given name, but only if it's different from the current value.

Can take less time on some version of PFRremote (where single attribute setting is about 50ms). Arguments are the same as [set\\_attribute\\_value\(\)](#).

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

```
class pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera(bitflow_idx=0,
                                                                    bitflow_camfile=None,
                                                                    pfcam_port=0)
```

Bases: [IPhotonFocusCamera](#), [BitFlowFrameGrabber](#)

BitFlow+PFCam interface to a PhotonFocus camera.

**Parameters**

- **bitflow\_idx** – board index, starting from 0
- **bitflow\_camfile** – if not None, a path to a valid camera file used for this frame grabber and camera combination; in this case, a temporary camera file is generated based on the provided one and used to change some otherwise unavailable camera parameters such as ROI and pixel bit depth (they are otherwise fixed to whatever is specified in the default camera file)
- **pfcam\_port** – port number for pfcam interface (can be learned by [list\\_cameras\(\)](#); port number is the first element of the camera data tuple) can also be a tuple (manufacturer, port), e.g., ("National Instruments", "port0").

**Error**

alias of [DeviceError](#)

**GrabberClass**

alias of [BitFlowFrameGrabber](#)

**open()**

Open connection to the camera

**setup\_acquisition**(mode='sequence', nframes=100, frame\_merge=None)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**class BufferManager**(cam)

Bases: `object`

Buffer manager: stores, constantly reads and re-schedules buffers, keeps track of acquired frames and buffer overflow events

**get\_status()**

Get counter status: tuple (acquired,)

**is\_running()**

Check if the buffer loop is running

**reset()**

Reset counter (on frame acquisition)

**start\_loop()**

Start buffer scheduling loop

**stop\_loop()**

Stop buffer scheduling loop

**FrameTransferError**

alias of `DefaultFrameTransferError`

**TimeoutError**

alias of `BitFlowTimeoutError`

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings**(settings)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**call\_command**(name, arg=0, error\_on\_missing=True)

Execute the given command with the given argument.

If the command doesn't exist and `error_on_missing==True`, raise error; otherwise, do nothing.

**clear\_acquisition()**

Clear all acquisition details and free all buffers

**close()**

Close connection to the camera

**enable\_CFR**(enabled=True)

Enable constant frame rate mode

**enable\_status\_line**(enabled=True)

Enable or disable status line

**fast\_shift\_roi**(*hstart=0, vstart=0*)

Shift ROI by only changing its origin, but keeping the shape the same.

Note that if the ROI is invalid, it won't be truncated (as is the standard behavior of `set_roi()`), which might lead to errors later.

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attribute\_values**(*root="", enum\_as\_str=True*)

Get values of all attributes with the given *root*

**get\_all\_attributes**(*copy=False*)

Return a dictionary of all available attributes.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute**(*name, error\_on\_missing=True*)

Get the camera attribute with the given name

**get\_attribute\_value**(*name, enum\_as\_str=True, error\_on\_missing=True, default=None*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not *None*, assume that *error\_on\_missing==False*. If *enum\_as\_str==True*, try to represent enums as their string values; If *name* points at a dictionary branch, return a dictionary with all values in this branch.

**get\_baudrate**()

Get the current baud rate

**get\_black\_level\_offset**()

Get the black level offset

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info**()

Get camera model data.

Return tuple (model, serial\_number, grabber\_info).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_exposure**()

Get current exposure

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings()**

Get acquisition timing.

Return tuple (`exposure`, `frame_period`).

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (`width`, `height`)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (`hstart`, `hend`, `vstart`, `vend`). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing**()

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range**()

Get the range of the new images.

Return tuple (*first, last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi**()

Get current ROI.

Return tuple (*hstart, hend, vstart, vend*).

**get\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_settings**(*include=0*)

Get dict {*name: value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_interleave**()

Check if the trigger interleave is on

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames, infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_CFR\_enabled**()

Check if the constant frame rate mode is enabled

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return `True`.

**is\_opened()**

Check if the device is connected

**is\_status\_line\_enabled()**

Check if the status line is on

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (`None` means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (`None` means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by `rng` (by default, all un-read images).

If `rng` is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. `missing_frame` determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied `rng` if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_all\_attribute\_values**(*settings, root="", truncate=True*)

Set values of all attributes with the given `root`.

If `truncate==True`, truncate value to lie within attribute range.

**set\_attribute\_value**(*name*, *value*, *truncate=True*, *error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and *error\_on\_missing==True*, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If *truncate==True*, truncate value to lie within attribute range.

**set\_black\_level\_offset**(*offset*)

Set the black level offset

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_exposure**(*exposure*)

Set current exposure

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt*, *include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_frame\_period**(*frame\_period*)

Set frame period (time between two consecutive frames in the internal trigger mode)

**set\_grabber\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

By default, all non-supplied parameters take extreme values.

**set\_trigger\_interleave**(*enabled*)

Set the trigger interleave option on or off

**setup\_max\_baudrate**()

Setup the maximal available baudrate

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as `:meth:`setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**update\_attribute\_value**(*name, value, error\_on\_missing=True, truncate=True*)

Set value of the attribute with a given name, but only if it's different from the current value.

Can take less time on some version of PFRemote (where single attribute setting is about 50ms). Arguments are the same as `set_attribute_value()`.

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

`pylablib.devices.PhotonFocus.PhotonFocus.check_grabber_association(cam)`

Check if PhotonFocus camera has correct association between the frame grabber and the PFRemote interface.

*cam* should be an opened instance of `PhotonFocusIMACamera` or `PhotonFocusSiSoCamera`. Note that this function changes camera parameters such as exposure, frame period, ROI, trigger source, and status line.

`pylablib.devices.PhotonFocus.PhotonFocus.get_status_lines(frames, check_transposed=True, drop_magic=True)`

Extract status lines (up to first 6 entries) from the given frames.

*frames* can be 2D array (one frame), 3D array (stack of frames, first index is frame number), or list of 1D or 2D arrays. Automatically check if the status line is present; return None if it's not. If *check\_transposed*==True, check for the case where the image is transposed (i.e., line becomes a column). If *drop\_magic*==True, remove



the first status line entry, which is simply a special number marking the status line presence. Return a 1D or 2D numpy array, where the first axis (if present) is the frame number, and the last is the status line entry. The entries after the magic are the frame index, timestamp (in us), missed trigger counters (up to 255), average frame value, and the integration time (in pixel clock cycles, which depend on the camera).

```
pylablib.devices.PhotonFocus.PhotonFocus.get_status_line_position(frame,
                                                                    check_transposed=True)
```

Check whether status line is present in the frame, and return its location.

Return tuple (*row*, *transposed*), where *row* is the status line row (can be -1 or -2) and *transposed* is True if the line is present in the transposed image. If no status line is found, return None. If *check\_transposed==True*, check for the case where the image is transposed (i.e., line becomes a column).

```
pylablib.devices.PhotonFocus.PhotonFocus.remove_status_line(frame, sl_pos='calculate',
                                                             policy='duplicate', copy=True)
```

Remove status line from the frame.

#### Parameters

- **frame** – a frame to process (2D or 3D numpy array; if 3D, the first axis is the frame number)
- **sl\_pos** – status line position (returned by `get_status_line_position()`); if equal to "calculate", calculate here; for a 3D array, assumed to be the same for all frames
- **policy** – determines way to deal with the status line; can be "keep" (keep as is), "cut" (cut off the status line row), "zero" (set it to zero), "median" (set it to the image median), or "duplicate" (set it equal to the previous row; default)
- **copy** – if True, make copy of the original frames; otherwise, attempt to remove the line in-place

```
pylablib.devices.PhotonFocus.PhotonFocus.find_skipped_frames(lines, step=1)
```

Check if there are skipped frames based on status line reading.

*step* specifies expected index step between neighboring frames.

Return list [(*idx*, *skipped*)], where *idx* is the index after which *skipped* frames were skipped.

```
class pylablib.devices.PhotonFocus.PhotonFocus.StatusLineChecker
```

Bases: `StatusLineChecker`

```
check_indices(indices, step=1)
```

Check if indices are consistent with the given step

```
get_framestamp(frames)
```

Get framestamps from status lines in the given frames

## Module contents

### pylablib.devices.Phy sikInstrumente package

#### Submodules

#### pylablib.devices.Phy sikInstrumente.base module

**exception** `pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteError`

Bases: *DeviceError*

Generic Physik Instrumente error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteBackendError(exc)`

Bases: *PhysikInstrumenteError, DeviceBackendError*

Generic Physik Instrumente backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** `pylablib.devices.PhysikInstrumente.base.GenericPIController(conn, auto_online=True)`

Bases: *ICommBackendWrapper, IMultiaxisStage*

Generic Physik Instrumente controller.

#### Parameters

- **conn** – connection parameters (usually port or a tuple containing port and baudrate)
- **auto\_online** – if `True`, switch to the online mode upon connection; in this online mode controller parameters are controlled remotely instead of the front panel (including external voltages), while in the offline mode most of the parameters are still controlled manually, and the remote connection is mostly used for readout

#### Error

alias of *PhysikInstrumenteError*

**open()**

Open the backend

**query(comm, multiline=False, reply=True)**

Query a single command to the controller.

If `multiline==True`, expect a multi-line reply and return a list with separate reply lines; otherwise, expect a single-line reply and raise an error if multi-line reply is received.

If `reply==False`, expect no reply at all (used for, e.g., set commands).

**query\_axis(comm, axis=None, subidx=None, kind='str')**

Query the given command for the given axis.

*axis* can be a single axis name (e.g., "A"), a list of axes, or `None`, which queries all axes. If *axis* is a single axis, simply return the corresponding value; otherwise, return a dict {*axis*: value}. *kind* can specify value kind: "str" (return as is), "float", "int", or "bool".

**set\_axis**(*comm, value, axis=None, subidx=None, reply=False*)

Query the given value for the given axis.

*value* can be a single value (set the same for all specified axes), a list of values (one per axis), or a dict {*axis*: *value*}. *axis* can be a single axis name (e.g., "A"), a list of axes, or None, which queries all axes. If *reply*==False, expect no reply.

**get\_id**()

Get the device ID string

**get\_help**()

Get the help for all commands; might take a long time on low-speed serial connections

**is\_online\_enabled**()

Check if online mode is enabled

**enable\_online**(*enable=True*)

Enable or disable online mode

**get\_axis\_parameter**(*pid, axis=None, kind='str'*)

Get value of the given parameter id for the given axis (all axes by default)

**set\_axis\_parameter**(*pid, value, axis=None, kind='str'*)

Get value of the given parameter id for the given axis (all axes by default)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**remap\_axes**(*mapping, accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** `pylablib.devices.PhysikInstrumente.base.PIE516`(*conn, auto\_online=True*)

Bases: [GenericPIController](#)

Physik Instrumente E-516 controller.

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **auto\_online** – if `True`, switch to the online mode upon connection; in this online mode controller parameters such as voltages or positions are controlled remotely instead of the front panel (including external voltages), while in the offline mode most of the parameters are still controlled manually, and the remote connection is mostly used for readout

**is\_servo\_enabled**(*axis=None*)

Check if the servo is enabled on the given axis (all axes by default)

**enable\_servo**(*enable=True, axis=None*)

Enable or disable servo on the given axis (all axes by default)

**is\_drift\_compensation\_enabled**(*axis=None*)

Check if the drift compensation is enabled on the given axis (all axes by default)

**enable\_drift\_compensation**(*enable=True, axis=None*)

Enable or disable drift compensation on the given axis (all axes by default)

**is\_velocity\_control\_enabled**(*axis=None*)

Check if the velocity control is enabled on the given axis (all axes by default)

**enable\_velocity\_control**(*enable=True, axis=None*)

Enable or disable velocity control on the given axis (all axes by default)

**get\_voltage\_setpoint**(*axis=None*)

Get the current voltage setpoint on the given axis (all axes by default)

**get\_voltage**(*axis=None*)

Get the actual voltage value on the given axis (all axes by default)

**set\_voltage**(*voltage*, *axis=None*)

Get the target voltage on the given axis (all axes by default)

**get\_voltage\_lower\_limit**(*axis=None*)

Get the lower output voltage limit on the given axis (all axes by default)

**set\_voltage\_lower\_limit**(*voltage*, *axis=None*)

Get the lower output voltage limit on the given axis (all axes by default)

**get\_voltage\_upper\_limit**(*axis=None*)

Get the upper output voltage limit on the given axis (all axes by default)

**set\_voltage\_upper\_limit**(*voltage*, *axis=None*)

Get the upper output voltage limit on the given axis (all axes by default)

**get\_velocity**(*axis=None*)

Get velocity on the given axis (all axes by default)

**set\_velocity**(*velocity*, *axis=None*)

Set velocity on the given axis (all axes by default)

**get\_position**(*axis=None*)

Get the current position on the given axis

**get\_target\_position**(*axis=None*)

Get the target motion position on the given axis

**move\_to**(*position*, *axis=None*)

Move the given axis to the given position

**move\_by**(*distance*, *axis=None*)

Move the given axis by the given distance

**stop**(*axis=None*)

Stop motion on the given axis (all axes by default)

**get\_position\_lower\_limit**(*axis=None*)

Get the lower position limit on the given axis (all axes by default)

**set\_position\_lower\_limit**(*position*, *axis=None*)

Get the lower position limit on the given axis (all axes by default)

**get\_position\_upper\_limit**(*axis=None*)

Get the upper position limit on the given axis (all axes by default)

**set\_position\_upper\_limit**(*position*, *axis=None*)

Get the upper position limit on the given axis (all axes by default)

**Error**

alias of [\*PhysikInstrumenteError\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**enable\_online**(*enable=True*)

Enable or disable online mode

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_axis\_parameter**(*pid, axis=None, kind='str'*)

Get value of the given parameter id for the given axis (all axes by default)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_help**()

Get the help for all commands; might take a long time on low-speed serial connections

**get\_id**()

Get the device ID string

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_online\_enabled**()

Check if online mode is enabled

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**query**(*comm, multiline=False, reply=True*)

Query a single command to the controller.

If *multiline==True*, expect a multi-line reply and return a list with separate reply lines; otherwise, expect a single-line reply and raise an error if multi-line reply is received.

If *reply==False*, expect no reply at all (used for, e.g., set commands).

**query\_axis**(*comm*, *axis=None*, *subidx=None*, *kind='str'*)

Query the given command for the given axis.

*axis* can be a single axis name (e.g., "A"), a list of axes, or *None*, which queries all axes. If *axis* is a single axis, simply return the corresponding value; otherwise, return a dict {*axis*: *value*}. *kind* can specify value kind: "str" (return as is), "float", "int", or "bool".

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_axis**(*comm*, *value*, *axis=None*, *subidx=None*, *reply=False*)

Query the given value for the given axis.

*value* can be a single value (set the same for all specified axes), a list of values (one per axis), or a dict {*axis*: *value*}. *axis* can be a single axis name (e.g., "A"), a list of axes, or *None*, which queries all axes. If *reply==False*, expect no reply.

**set\_axis\_parameter**(*pid*, *value*, *axis=None*, *kind='str'*)

Get value of the given parameter id for the given axis (all axes by default)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** `pylablib.devices.PhysikInstrumente.base.PIE515`(*conn*, *auto\_online=True*)

Bases: [IMultiaxisStage](#), [SCPIDevice](#)

Physik Instrumente E-515 controller.

#### Parameters

- **conn** – connection parameters (usually port or a tuple containing port and baudrate)
- **auto\_online** – if *True*, switch to the online mode upon connection; in this online mode controller parameters are controlled remotely instead of the front panel (including external voltages), while in the offline mode most of the parameters are still controlled manually, and the remote connection is mostly used for readout

#### Error

alias of [PhysikInstrumenteError](#)

#### ReraiseError

alias of [PhysikInstrumenteBackendError](#)

**open**()

Open the connection

**close**()

Close the connection

**is\_online\_enabled**()

Check if online mode is enabled

**enable\_online**(*enable=True, safe=False*)

Enable or disable online mode.

If *safe==True* and *enable==True*, set the current voltage and position setpoints to be equal to the currently read values; this avoids sudden change of output voltages when enabling the online mode. Note that this only works if all servo modes are off (enabling online mode always forcibly turns them off, which might lead to the output voltage jump).

**get\_current\_axis**()

Select the current measurement channel

**select\_axis**(*axis*)

Select the current default axis

**is\_servo\_enabled**(*axis=None*)

Check if the servo is enabled on the given axis (current axis by default)

**enable\_servo**(*enable=True, axis=None*)

Enable or disable servo on the given axis (current axis by default)

**get\_voltage\_setpoint**(*axis=None*)

Get the current voltage setpoint on the given axis (current axis by default)

**get\_voltage**(*axis=None*)

Get the actual voltage value on the given axis (current axis by default)

**set\_voltage**(*voltage, axis=None*)

Get the target voltage on the given axis (current axis by default)

**get\_voltage\_lower\_limit**(*axis=None*)

Get the lower output voltage limit on the given axis (current axis by default)

**set\_voltage\_lower\_limit**(*voltage, axis=None*)

Get the lower output voltage limit on the given axis (current axis by default)

**get\_voltage\_upper\_limit**(*axis=None*)

Get the upper output voltage limit on the given axis (current axis by default)

**set\_voltage\_upper\_limit**(*voltage, axis=None*)

Get the upper output voltage limit on the given axis (current axis by default)

**get\_position**(*axis=None*)

Get current measured position on the given axis (current axis by default)

**get\_target\_position**(*axis=None*)

Get the target motion position on the given axis

**move\_to**(*position, axis=None*)

Move the given axis to the given position

**move\_by**(*distance, axis=None*)

Move the given axis by the given distance

**get\_position\_lower\_limit**(*axis=None*)

Get the lower position limit on the given axis (current axis by default)

**set\_position\_lower\_limit**(*position, axis=None*)

Get the lower position limit on the given axis (current axis by default)



**get\_position\_upper\_limit**(*axis=None*)

Get the upper position limit on the given axis (current axis by default)

**set\_position\_upper\_limit**(*position, axis=None*)

Get the upper position limit on the given axis (current axis by default)

**BackendError**

alias of *DeviceBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {**name**: **value**} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {**name**: **value**} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {**name**: **value**} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**remap\_axes**(*mapping, accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**reset()**

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer()**

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.PrincetonInstruments package

#### Submodules

#### pylablib.devices.PrincetonInstruments.picam module

**class** pylablib.devices.PrincetonInstruments.picam.**LibraryController**(*lib*)

Bases: *LibraryController*

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result*, *uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result*=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (*init\_result*, *open\_result*, *opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result*=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

**class** pylablib.devices.PrincetonInstruments.picam.**TCameraInfo**(*name*, *serial\_number*, *model*,  
*interface*)

Bases: *tuple*

**interface**

**model**

**name**

**serial\_number**

pylablib.devices.PrincetonInstruments.picam.**list\_cameras**()

List all cameras available through Picam interface

pylablib.devices.PrincetonInstruments.picam.**get\_cameras\_number**()

Get number of connected Picam cameras

**class** pylablib.devices.PrincetonInstruments.picam.**TR0IConstraints**(*flags*, *nrois*, *xrng*, *wrng*, *xbins*,  
*yrng*, *hrng*, *ybins*)

Bases: *tuple*

**flags****hrng****nrois****wrng****xbins****xrng****ybins****yrng****class** `pylablib.devices.PrincetonInstruments.picam.PicamAttribute(handle, pid)`Bases: `object`

Object representing an Picam camera parameter.

Allows to query and set values and get additional information. Usually created automatically by an *PicamCamera* instance, but could be created manually.**Parameters**

- **handle** – camera handle
- **pid** – parameter id of the attribute

**name**

attribute name

**kind**

attribute kind; can be "Integer", "Large Integer", "Floating Point", "Enumeration", "Boolean", or "Rois"

**exists**

whether attribute is available on the current hardware

**Type**`bool`**relevant**

whether attribute value is applicable to the hardware

**Type**`bool`**read\_directly**whether value can be read directly from the device; if True, then `get_value()` will automatically use the appropriate method**Type**`bool`**value\_access**

value access kind, which shows whether value can be written

**Type**`str`

**writable**

whether value is read-only

**Type**

bool

**default**

default parameter value (only for writable parameters)

**can\_set\_online**

whether value can be changed during acquisition

**Type**

bool

**cons\_type**

constraint type, e.g., "Collection", "Range", or "None"

**Type**

str

**cons\_permanent**

whether the constraint is permanent, or dependent on other parameters; if `False`, then use [`update\_limits\(\)`](#) to update the constraints

**Type**

bool

**cons\_error**

whether setting the out-of-range parameter causes error or just warning

**Type**

bool

**cons\_novalid**

whether no parameter value is valid

**Type**

bool

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**inc**

minimal attribute increment value (if applicable)

**Type**

float or int

**cons\_excluded**

list of special parameters which are within the range but are excluded

**cons\_included**

list of special parameters which are outside the range but are included

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**update\_limits**(*force=False*)

Update attribute constraints.

If *force==False* and the constraints are permanent, skip the update.

**truncate\_value**(*value*)

Truncate value to lie within attribute limits

**get\_value**(*enum\_as\_str=True*)

Get attribute value.

If *enum\_as\_str==True*, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_value**(*value, truncate=True*)

Get attribute value.

If *truncate==True*, automatically truncate value to lie within allowed range.

```
class pylablib.devices.PrincetonInstruments.picam.TDeviceInfo(name, serial_number, model,
                                                             interface)
```

Bases: `tuple`

**interface****model****name****serial\_number**

```
class pylablib.devices.PrincetonInstruments.picam.TFrameInfo(frame_index, timestamp_start,
                                                             timestamp_end, framestamp)
```

Bases: `tuple`

**frame\_index****framestamp****timestamp\_end****timestamp\_start**

**class** pylablib.devices.PrincetonInstruments.picam.PicamCamera(*serial\_number=None*)

Bases: *IBinROICamera*, *IExposureCamera*, *IAttributeCamera*

Generic Picam camera interface.

**Parameters**

**serial\_number** – camera serial number; if None, connect to the first non-used camera

**Error** = <Mock name='mock.PicamError' id='140527574123344'>

**TimeoutError** = <Mock spec='str' id='140527570011344'>

**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_attribute\_value**(*name*, *error\_on\_missing=True*, *default=None*, *enum\_as\_str=True*)

Get value of an attribute with the given name.

If the value doesn't exist or can not be read and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not None, assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. If *enum\_as\_str==True*, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_attribute\_value**(*name*, *value*, *truncate=True*, *error\_on\_missing=True*)

Set value of an attribute with the given name.

If the value doesn't exist or can not be written and *error\_on\_missing==True*, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). If *truncate==True*, truncate value to lie within attribute range.

**get\_all\_attribute\_values**(*root=""*, *enum\_as\_str=True*)

Get values of all attributes with the given *root*

**set\_all\_attribute\_values**(*settings*, *root=""*, *truncate=True*)

Set values of all attributes with the given *root*.

If *truncate==True*, truncate value to lie within attribute range.

**get\_device\_info()**

Get camera information.

Return tuple (vendor, model, serial\_number, bus\_type).

**get\_pixel\_size()**

Get camera pixel size (in m)

**enable\_metadata**(*enable=True*)

Enable or disable metadata

**is\_metadata\_enabled**(*individual=False*)

Check if metadata is enabled.

If *individual==True*, return individual metadata info (time\_stamp\_start, time\_stamp\_end, frame\_stamp, gate\_delay, modulation\_phase). Otherwise, return simply True or False depending on whether the basic group (time- and frame-stamps) is enabled. In this case, if the value is inconsistent with either for the groups, fix this to be consistent.



**get\_exposure()**

Get current exposure

**set\_exposure(*exposure*)**

Set camera exposure

**get\_frame\_period(*per\_readout=False*)**

Get frame period (time between two consecutive frames in the internal trigger mode)

If *per\_readout*==True, return time difference between readouts, which can contain more than one frame; otherwise, return average time per frame (keep in mind that the frames still come in single unbroken readout).

**get\_frame\_timings(*per\_readout=False*)**

Get acquisition timing.

Return tuple (*exposure*, *frame\_period*). If *per\_readout*==True, frame period difference between readouts, which can contain more than one frame; otherwise, it is the time per frame (keep in mind that the frames still come in single unbroken readout).

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*, *hbin=1*, *vbin=1*)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**setup\_acquisition(*mode='sequence'*, *nframes=100*)**

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). *nframes* sets up number of frame buffers. If there are multiple frames per readout, it still means the number of frames, and the number of readouts is set up to contain all required frames (e.g., 10 frames per readout and 15 frames result in 2 readouts).

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\**args*, \*\**kwargs*)**

Start acquisition.

Can take the same keyword parameters as *meth: ``setup\_acquisition``*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None).

Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_attributes(copy=False)**

Return a dictionary of all available attributes.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by *get\_frame\_info\_fields()*; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (`first`, `last`) with images range (first inclusive). If no images are available, return `None`. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {`name`: `value`} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if `None`, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return `True`.

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (`None` means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (`None` means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes) If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==`True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If *peek*==`True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==`True`, return tuple (*frames*, *infos*), where *infos* is a list of `TFrameInfo` instances describing frame index and frame metadata, which contains start and stop timestamps, and framestamp; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is `None`. if *return\_rng*==`True`, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

## Module contents

### pylablib.devices.Rigol package

#### Submodules

#### pylablib.devices.Rigol.base module

**exception** `pylablib.devices.Rigol.base.GenericRigolError`

Bases: `DeviceError`

Generic Rigol error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Rigol.base.GenericRigolBackendError(*exc*)

Bases: [GenericRigolError](#), [DeviceBackendError](#)

Rigol backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

## pylablib.devices.Rigol.power\_supply module

**class** pylablib.devices.Rigol.power\_supply.DP1116A(*addr*)

Bases: [SCPIDevice](#)

Rigol DP1116A DC power supply.

**Parameters**

**addr** – device address (usually a VISA name).

**Error**

alias of [GenericRigolError](#)

**ReraiseError**

alias of [GenericRigolBackendError](#)

**is\_output\_enabled()**

Check if the output is enabled

**enable\_output**(*enable=True*)

Enable or disable the output

**get\_output\_range()**

Get output range.

Can be either "16V" (16V/10A) or "32V" (32V/5A).

**set\_output\_range**(*value='16V'*)

Set output range.

Can be either "16V" (16V/10A) or "32V" (32V/5A).

**get\_voltage\_setpoint()**

Get output voltage setpoint

**get\_voltage()**

Get the actual output voltage

**set\_voltage(value)**

Set output voltage setpoint

**get\_current\_setpoint()**

Get output current setpoint

**get\_current()**

Get the actual output current

**set\_current(value)**

Set output current setpoint

**get\_power()**

Get the actual output power

**get\_ovp\_threshold()**

Get over-voltage protection threshold

**set\_ovp\_threshold(value)**

Set over-voltage protection threshold

**is\_ovp\_enabled()**

Check if the over-voltage protection is enabled

**enable\_ovp(enable=True)**

Enable or disable the over-voltage protection

**get\_ocp\_threshold()**

Get over-current protection threshold

**set\_ocp\_threshold(value)**

Set over-current protection threshold

**is\_ocp\_enabled()**

Check if the over-current protection is enabled

**enable\_ocp(enable=True)**

Enable or disable the over-current protection

**BackendError**

alias of [DeviceBackendError](#)

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {**name**: **value**} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static** `get_arg_type(arg)`

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static** `parse_array_data(data, fmt, include_header=False)`

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this



callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive *write()* operations are bundled together with ; delimiter. The actual write is performed at the *read()/ask()* operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform *wait\_sync()*), 'dev' (perform *wait\_dev()*) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.

- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.SiliconSoftware package

#### Submodules

#### pylablib.devices.SiliconSoftware.fgrab module

`class pylablib.devices.SiliconSoftware.fgrab.TBoardInfo(name, full_name, serial)`

Bases: `tuple`

`full_name`

`name`

`serial`

`pylablib.devices.SiliconSoftware.fgrab.TFullBoardInfo`

alias of `TBoardInfo`

`pylablib.devices.SiliconSoftware.fgrab.get_board_info(board, full_desc=False)`

Get board info for a given index (starting from 0)

`pylablib.devices.SiliconSoftware.fgrab.list_boards(full_desc=False)`

List all boards available through Silicon Software interface

`pylablib.devices.SiliconSoftware.fgrab.get_boards_number()`

List number of connected Silicon Software boards

```
class pylablib.devices.SiliconSoftware.fgrab.TAppletInfo(name, file)
```

Bases: `tuple`

**file**

**name**

```
class pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo(name, uid, desc, category, platform,
                                                             tags, version, path, file, flags, info)
```

Bases: `tuple`

**category**

**desc**

**file**

**flags**

**info**

**name**

**path**

**platform**

**tags**

**uid**

**version**

```
pylablib.devices.SiliconSoftware.fgrab.list_applets(board, full_desc=False, valid=True,
                                                    on_board=False)
```

List all applets available for this board.

*board* is the board index (starting from 0) given by its position in the list returned by `list_boards()`. If `full_desc==True`, return full description for each applet; otherwise, return only name and file name. If `valid==True`, list only valid and compatible applets; otherwise, list all applets. If `on_board==True`, list applets running on board; otherwise, list all applets contained in the system.

```
pylablib.devices.SiliconSoftware.fgrab.get_applet_info(board, **kwargs)
```

Return full information for an applet with the given parameters (e.g., name, or full path)

```
class pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute(fg, aid, port=0, system=False,
                                                            idx=None)
```

Bases: `object`

Object representing an Silicon Software frame grabber parameter.

Allows to query and set values and get additional information. Usually created automatically by an `:class:` instance, but could be created manually.

#### Parameters

- **fg** – opened frame grabber handle
- **aid** – attribute ID
- **port** – camera port within the frame grabber

- **system** – if True, this is a system attribute; otherwise, it is a camera attribute
- **idx** – if `system==True` and `fg` is None, it can specify a board index for a not yet opened grabber

**name**

attribute name

**kind**

attribute kind; can be "i32", "i64", "u32", "u64", "f64", or "str"

**min**

minimal attribute value (if applicable)

**Type**

float or int

**max**

maximal attribute value (if applicable)

**Type**

float or int

**inc**

minimal attribute increment value (if applicable)

**Type**

float or int

**ivalues**

list of possible integer values for enum attributes

**values**

list of possible text values for enum attributes

**labels**

dict {label: index} which shows all possible values of an enumerated attribute and their corresponding numerical values

**ilabels**

dict {index: label} which shows labels corresponding to numerical values of an enumerated attribute

**update\_limits()**

Update minimal and maximal attribute limits and return tuple (min, max, inc)

**truncate\_value(value)**

Truncate value to lie within attribute limits

**get\_value(enum\_as\_str=True)**

Get attribute value.

If `enum_as_str==True`, return enum-style values as strings; otherwise, return corresponding integer values.

**set\_value(value, truncate=True)**

Get attribute value.

If `truncate==True`, automatically truncate value to lie within allowed range.

```
class pylablib.devices.SiliconSoftware.fgrab.TDeviceInfo(applet_info, system_info,
                                                         software_version)
```

Bases: `tuple`

`applet_info`

`software_version`

`system_info`

```
class pylablib.devices.SiliconSoftware.fgrab.TFrameInfo(frame_index, framestamp, timestamp,
                                                         timestamp_long)
```

Bases: `tuple`

`frame_index`

`framestamp`

`timestamp`

`timestamp_long`

```
class pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber(siso_board=0,
                                                                            siso_applet=None,
                                                                            siso_port=0,
                                                                            siso_detector_size=None,
                                                                            do_open=True,
                                                                            **kwargs)
```

Bases: `IGrabberAttributeCamera`, `IROIcamera`

Generic Silicon Software frame grabber interface.

Compared to `SiliconSoftwareCamera`, has more permissive initialization arguments, which simplifies its use as a base class for expanded cameras.

#### Parameters

- **siso\_board** – board index, starting from 0; available boards can be learned by `list_boards()`
- **siso\_applet** – applet name, which can be learned by `list_applets()`; usually, a simple applet like "DualLineGray16" or "MediumLineGray16" are most appropriate; can be either an applet name, or a direct path to the applet DLL
- **siso\_port** – port number, if several ports are supported by the grabber and the applet
- **siso\_detector\_size** – if not None, can specify the maximal detector size; by default, use the maximal available for the frame grabber (usually, 16384x16384)

```
Error = <Mock name='mock.SiliconSoftwareError' id='140527586804624'>
```

```
TimeoutError = <Mock spec='str' id='140527586806736'>
```

```
open()
```

Open connection to the camera

```
close()
```

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_all\_grabber\_attribute\_values**(*root*="", *\*\*kwargs*)

Get values of all frame grabber attributes with the given *root*.

Additional arguments are passed to *get\_value* methods of individual attributes.

**set\_all\_grabber\_attribute\_values**(*settings*, *root*="", *\*\*kwargs*)

Set values of all frame grabber attributes with the given *root*.

Additional arguments are passed to *set\_value* methods of individual attributes.

**get\_system\_info()**

Get the dictionary with all system information parameters

**get\_genicam\_info\_xml()**

Get description in Genicam-compatible XML format

**get\_device\_info()**

Get camera model data.

Return tuple (*applet\_info*, *system\_info*, *software\_version*) with the board serial number and an the interface type (e.g., "1430" for NI PCIe-1430)

**set\_frame\_merge**(*frame\_merge*=1)**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (*width*, *height*)

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi**(*hstart*=0, *hend*=None, *vstart*=0, *vend*=None)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_grabber\_roi**(*hstart*=0, *hend*=None, *vstart*=0, *vend*=None)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_grabber\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**class BufferManager**(*fg, siso\_port*)

Bases: `object`

Frame buffer manager which controls and schedules the buffer and the buffer copying loop

**allocate**(*nframes, frame\_size*)

Allocate and schedule buffers with the given number and size

**deallocate**()

Deallocate and remove the buffers

**start\_loop**(*run\_nframes*)

Start the copying loop and, optionally, run the acquisition loop with the given number of frames

**stop\_loop**()

Stop the copying loop

**get\_status**()

Get acquisition status.

Return tuple (*nread, oldest\_valid\_buffer, nacq, debug\_info*)

**get\_frames\_data**(*idx, nframes=1*)

Get buffer chunk addresses for the given number of frames starting from the given index

**setup\_camlink\_pixel\_format**(*bits\_per\_pixel=8, taps=1, output\_fmt=None, fmt=None, bit\_alignment='right\_custom'*)

Set up CameraLink pixel format.

If *fmt* is `None`, use supplied *bits\_per\_pixel* (8, 10, 12, 14, or 16) and *taps* (1 or 2) to figure out the format; otherwise, *fmt* should be a numerical (e.g., 210) or string (e.g., "FG\_CL\_MEDIUM\_10\_BIT") format. *output\_fmt* specifies the result frame format; if `None`, use grayscale with the given *bits\_per\_pixel* if *fmt* is `None`, or 16 bit grayscale otherwise. *bit\_alignment* can specify the alignment of the resulting data (applicable when *bits\_per\_pixel* is not divisible by 8); can be "left", "right", "right\_custom" (explicitly calculate and set the number of bits to shift by whenever possible; this solves some issues on ME5 cards), or an integer specifying the number of bits to shift.

**get\_camlink\_pixel\_format**()

Get CamLink pixel format and the output pixel format as a tuple

**get\_available\_camlink\_pixel\_formats**()

Get all available CamLink pixel formats and the output pixel formats as a tuple of 2 lists

**setup\_acquisition**(*mode*='sequence', *nframes*=100)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that *IMAQCamera.acquisition\_in\_progress()* would still return True in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**clear\_acquisition**()

Clear all acquisition details and free all buffers

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**acquisition\_in\_progress**()

Check if acquisition is in progress

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_grabber\_attributes**(*copy*=False)

Return a dictionary of all available frame grabber grabber\_attributes.

If *copy*==True, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields**()

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".



**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_grabber\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_grabber\_attribute\_value(name, error\_on\_missing=True, default=None, \*\*kwargs)**

Get value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not None, automatically assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. Additional arguments are passed to *get\_value* methods of the individual attribute.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return *None*. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1*, *frame\_timeout=5.0*, *missing\_frame='skip'*, *return\_info=False*, *buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**pausing\_acquisition**(*clear=None*, *stop=True*, *setup\_after=None*, *start\_after=True*,  
*combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None*, *peek=False*, *missing\_frame='skip'*, *return\_info=False*,  
*return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False*, *return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes) If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_grabber\_attribute\_value**(*name, value, error\_on\_missing=True, \*\*kwargs*)

Set value of a frame grabber attribute with the given name.

If the value doesn't exist and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). Additional arguments are passed to `set_value` methods of the individual attribute.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (timeout, frame\_timeout), in which case the call times out if the total time exceeds timeout, or a single frame wait exceeds frame\_timeout. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera`(board, applet=None, port=0, detector\_size=None)

Bases: `SiliconSoftwareFrameGrabber`

Generic Silicon Software frame grabber interface.

#### Parameters

- **board** – board index, starting from 0; available boards can be learned by `list_boards()`
- **applet** – applet name, which can be learned by `list_applets()`; usually, a simple applet like "DualLineGray16" or "MediumLineGray16" are most appropriate; can be either an applet name, or a direct path to the applet DLL
- **port** – port number, if several ports are supported by the camera and the applet
- **detector\_size** – if not None, can specify the maximal detector size; by default, use the maximal available for the frame grabber (usually, 16384x16384)

**class** `BufferManager`(fg, siso\_port)

Bases: `object`

Frame buffer manager which controls and schedules the buffer and the buffer copying loop

**allocate**(nframes, frame\_size)

Allocate and schedule buffers with the given number and size

**deallocate**()

Deallocate and remove the buffers

**get\_frames\_data**(idx, nframes=1)

Get buffer chunk addresses for the given number of frames starting from the given index

**get\_status**()

Get acquisition status.

Return tuple (nread, oldest\_valid\_buffer, nacq, debug\_info)

**start\_loop**(run\_nframes)

Start the copying loop and, optionally, run the acquisition loop with the given number of frames

**stop\_loop**()

Stop the copying loop

**Error** = <Mock name='mock.SiliconSoftwareError' id='140527586804624'>

**FrameTransferError**

alias of `DefaultFrameTransferError`

**TimeoutError** = <Mock spec='str' id='140527586806736'>

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear all acquisition details and free all buffers

**close()**

Close connection to the camera

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_all\_grabber\_attribute\_values(root="", \*\*kwargs)**

Get values of all frame grabber attributes with the given *root*.

Additional arguments are passed to *get\_value* methods of individual attributes.

**get\_all\_grabber\_attributes(copy=False)**

Return a dictionary of all available frame grabber *grabber\_attributes*.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_available\_camlink\_pixel\_formats()**

Get all available CamLink pixel formats and the output pixel formats as a tuple of 2 lists

**get\_camlink\_pixel\_format()**

Get CamLink pixel format and the output pixel format as a tuple

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_info()**

Get camera model data.

Return tuple (*applet\_info*, *system\_info*, *software\_version*) with the board serial number and an the interface type (e.g., "1430" for NI PCIe-1430)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_genicam\_info\_xml()**

Get description in Genicam-compatible XML format

**get\_grabber\_attribute(name, error\_on\_missing=True)**

Get the camera attribute with the given name

**get\_grabber\_attribute\_value(name, error\_on\_missing=True, default=None, \*\*kwargs)**

Get value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not None, automatically assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. Additional arguments are passed to `get_value` methods of the individual attribute.

**get\_grabber\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_grabber\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_grabber\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**get\_roi\_limits(*hbin=1*, *vbin=1*)**

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_system\_info()**

Get the dictionary with all system information parameters

**grab(*nframes=1*, *frame\_timeout=5.0*, *missing\_frame='skip'*, *return\_info=False*, *buff\_size=None*)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return `True`.

**is\_opened()**

Check if the device is connected

**open()**

Open connection to the camera

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (`None` means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (`None` means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by `rng` (by default, all un-read images).

If `rng` is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. `missing_frame` determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied `rng` if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_all\_grabber\_attribute\_values**(*settings, root="", \*\*kwargs*)

Set values of all frame grabber attributes with the given `root`.

Additional arguments are passed to `set_value` methods of individual attributes.



**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt*, *include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_frame\_merge**(*frame\_merge=1*)

**set\_grabber\_attribute\_value**(*name*, *value*, *error\_on\_missing=True*, *\*\*kwargs*)

Set value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). Additional arguments are passed to *set\_value* methods of the individual attribute.

**set\_grabber\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**set\_roi**(*hstart=0*, *hend=None*, *vstart=0*, *vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**setup\_acquisition**(*mode*='sequence', *nframes*=100)

Setup acquisition mode.

*mode* can be either "snap" (single frame or a fixed number of frames) or "sequence" (continuous acquisition). (note that `IMAQCamera.acquisition_in_progress()` would still return True in this case, even though new frames are no longer acquired). *nframes* sets up number of frame buffers.

**setup\_camlink\_pixel\_format**(*bits\_per\_pixel*=8, *taps*=1, *output\_fmt*=None, *fmt*=None, *bit\_alignment*='right\_custom')

Set up CameraLink pixel format.

If *fmt* is None, use supplied *bits\_per\_pixel* (8, 10, 12, 14, or 16) and *taps* (1 or 2) to figure out the format; otherwise, *fmt* should be a numerical (e.g., 210) or string (e.g., "FG\_CL\_MEDIUM\_10\_BIT") format. *output\_fmt* specifies the result frame format; if None, use grayscale with the given *bits\_per\_pixel* if *fmt* is None, or 16 bit grayscale otherwise. *bit\_alignment* can specify the alignment of the resulting data (applicable when *bits\_per\_pixel* is not divisible by 8); can be "left", "right", "right\_custom" (explicitly calculate and set the number of bits to shift by whenever possible; this solves some issues on ME5 cards), or an integer specifying the number of bits to shift.

**snap**(*timeout*=5.0, *return\_info*=False)

Snap a single frame

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as `:meth:`setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since*='lastread', *nframes*=1, *timeout*=20.0, *error\_on\_stopped*=False)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*=True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

## Module contents

### pylablib.devices.Sirah package

#### Submodules

#### pylablib.devices.Sirah.Matisse module

```
class pylablib.devices.Sirah.Matisse.TThinCtlParameters(setpoint, P, I, avg)
```

```
    Bases: tuple
```

```
    I
```

```
    P
```

```
    avg
```

```
    setpoint
```

```
class pylablib.devices.Sirah.Matisse.TPiezoetDriveParameters(amplitude, rate, oversamp)
```

```
    Bases: tuple
```

```
    amplitude
```

```
    oversamp
```

```
    rate
```

```
class pylablib.devices.Sirah.Matisse.TPiezoetFeedbackParameters(P, avg, phase)
```

```
    Bases: tuple
```

```
    P
```

```
    avg
```

```
    phase
```

```
class pylablib.devices.Sirah.Matisse.TPiezoetFeedforwardParameters(ampl, phase)
```

```
    Bases: tuple
```

```
    ampl
```

```
    phase
```

```
class pylablib.devices.Sirah.Matisse.TSlowpiezoCtlParameters(setpoint, P, I, freeP)
```

```
    Bases: tuple
```

```
    I
```

```
    P
```

```
    freeP
```

```
    setpoint
```

```
class pylablib.devices.Sirah.Matisse.TFastpiezoCtlParameters(setpoint, I, lockpoint)
```

```
    Bases: tuple
```

**I**

**lockpoint**

**setpoint**

```
class pylablib.devices.Sirah.Matisse.TRefcellWaveformParameters(lower_limit, upper_limit,
                                                                oversamp, mode)
```

Bases: [tuple](#)

**lower\_limit**

**mode**

**oversamp**

**upper\_limit**

```
class pylablib.devices.Sirah.Matisse.TScanMode(falling, stop_lower, stop_upper)
```

Bases: [tuple](#)

**falling**

**stop\_lower**

**stop\_upper**

```
class pylablib.devices.Sirah.Matisse.TScanParameters(device, mode, lower_limit, upper_limit,
                                                       rise_speed, fall_speed)
```

Bases: [tuple](#)

**device**

**fall\_speed**

**lower\_limit**

**mode**

**rise\_speed**

**upper\_limit**

```
class pylablib.devices.Sirah.Matisse.SirahMatisse(addr, use_mc_server='auto')
```

Bases: [SCPIDevice](#)

Sirah Matisse laser control.

#### Parameters

- **addr** – device address (usually a VISA name).
- **use\_mc\_server** – determines whether Matisse Commander server is used for the communication (it has somewhat different command format); if "auto", assumed to be True for network connections and False otherwise

#### Error

alias of [GenericSirahError](#)

#### ReraiseError

alias of [GenericSirahBackendError](#)

**close()**

Close the backend

**ask(\*args, \*\*kwargs)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If `read_echo==True`, assume that the device first echoes the input and skip it.

**get\_diode\_power()**

Get the current laser resonator power

**get\_diode\_power\_waveform()**

Get the current laser resonator power waveform

**get\_diode\_power\_lowlevel()**

Get the low-level cutoff current laser resonator power

**set\_diode\_power\_lowlevel(*cutoff*)**

Set the low-level cutoff current laser resonator power

**get\_thinnet\_power()**

Get the current thin etalon reflex power

**get\_refcell\_waveform()**

Get the reference cell signal waveform

**bifi\_get\_position()**

Get the current position of the birefringent filter motor

**bifi\_get\_range()**

Get the maximum position of the birefringent filter motor

**bifi\_get\_status\_n()**

Get the numerical status of the birefringent filter motor

**bifi\_get\_status()**

Get the parsed status of the birefringent filter motor.

Return tuple (code, bits) with, correspondingly, the general status/error code (e.g., "idle", "moving\_abs", or "position\_out\_of\_range"), and a set of active status bits (e.g., "moving", "error", or "limit\_sw1").

**bifi\_clear\_errors()**

Clear the indicated errors of the birefringent filter motor

**bifi\_is\_moving()**

Check if the birefringent filter is moving

**bifi\_wait\_move(*timeout=30.0*)**

Wait until birefringent filter is done moving

**bifi\_move\_to(*position*, *wait=True*, *wait\_timeout=30.0*)**

Move the birefringent filter to the current position

**bifi\_stop()**

Stop the birefringent filter motor

**bifi\_home**(*wait=True, wait\_timeout=30.0*)

Home the birefringent filter motor

**thinet\_get\_position**()

Get the current position of the thin etalon motor

**thinet\_get\_range**()

Get the maximum position of the thin etalon motor

**thinet\_get\_status\_n**()

Get the numerical status of the thin etalon motor

**thinet\_get\_status**()

Get the parsed status of the thin etalon motor.

Return tuple (code, bits) with, correspondingly, the general status/error code (e.g., "idle", "moving\_abs", or "position\_out\_of\_range"), and a set of active status bits (e.g., "moving", "error", or "limit\_sw1").

**thinet\_clear\_errors**()

Clear the indicated errors of the thin etalon motor

**thinet\_is\_moving**()

Check if the thin etalon is moving

**thinet\_wait\_move**(*timeout=30.0*)

Wait until thin etalon is done moving

**thinet\_move\_to**(*position, wait=True, wait\_timeout=30.0*)

Move the thin etalon to the current position

**thinet\_stop**()

Stop the thin etalon motor

**thinet\_home**(*wait=True, wait\_timeout=30.0*)

Home the thin etalon motor

**get\_thinet\_ctl\_status**()

Get thin etalon lock status ("run" or "stop")

**set\_thinet\_ctl\_status**(*status='run'*)

Set thin etalon lock status ("run" or "stop")

**get\_thinet\_error\_signal**()

Get error signal of the thin etalon lock (emulated when not available on older firmware)

**get\_thinet\_ctl\_params**()

Get thin etalon lock control parameters.

Return tuple (setpoint, P, I, avg).

**set\_thinet\_ctl\_params**(*setpoint=None, P=None, I=None, avg=None*)

Set thin etalon lock control parameters.

Any parameters which are None remain unchanged.

**get\_piezoet\_ctl\_status**()

Get piezo etalon lock status ("run" or "stop")

**set\_piezoet\_ctl\_status**(*status='run'*)

Set piezo etalon lock status ("run" or "stop")

**get\_piezoet\_position**()

Get piezo etalon DC position

**set\_piezoet\_position**(*value*)

Set piezo etalon lock DC position

**get\_piezoet\_drive\_params**()

Get piezo etalon drive parameters.

Return tuple (amplitude, rate, oversamp).

**set\_piezoet\_drive\_params**(*amplitude=None, rate=None, oversamp=None*)

Set piezo etalon drive parameters.

*oversamp* should be between 8 and 32. *rate* can take values "8k", "32k", "48k", or "96k". Any parameters which are None remain unchanged.

**get\_piezoet\_feedback\_params**()

Get piezo etalon feedback parameters.

Return tuple (P, avg, phase) (phase is integer between 0 and oversampling).

**set\_piezoet\_feedback\_params**(*P=None, avg=None, phase=None*)

Set piezo etalon feedback parameters.

Phase is integer between 0 and oversampling. Any parameters which are None remain unchanged.

**get\_piezoet\_feedforward\_params**()

Get piezo etalon feedforward parameters.

Return tuple (amp, phase) (phase is integer between 0 and oversampling).

**set\_piezoet\_feedforward\_params**(*amp=None, phase=None*)

Set piezo etalon feedforward parameters.

Phase is integer between 0 and oversampling. Any parameters which are None remain unchanged.

**get\_slowpiezo\_ctl\_status**()

Get slow piezo lock status ("run" or "stop")

**set\_slowpiezo\_ctl\_status**(*status='run'*)

Set slow piezo lock status ("run" or "stop")

**get\_slowpiezo\_position**()

Get slow piezo DC position

**set\_slowpiezo\_position**(*value*)

Set slow piezo DC position

**get\_slowpiezo\_ctl\_params**()

Get slow piezo lock control parameters.

Return tuple (setpoint, P, I, freeP).

**set\_slowpiezo\_ctl\_params**(*setpoint=None, P=None, I=None, freeP=None*)

Set slow piezo lock control parameters.

Any parameters which are None remain unchanged.

**get\_fastpiezo\_ctl\_status()**

Get fast piezo lock status ("run" or "stop")

**set\_fastpiezo\_ctl\_status**(*status='run'*)

Set fast piezo lock status ("run" or "stop")

**is\_fastpiezo\_locked()**

Check if the fast piezo is locked (output is between 5% and 95%)

**get\_fastpiezo\_position()**

Get fast piezo DC position between 0 and 1

**set\_fastpiezo\_position**(*value*)

Set fast piezo DC position between 0 and 1

**get\_fastpiezo\_ctl\_params()**

Get fast piezo lock control parameters.

Return tuple (setpoint, I, lockpoint).

**set\_fastpiezo\_ctl\_params**(*setpoint=None, I=None, lockpoint=None*)

Set fast piezo lock control parameters.

Any parameters which are None remain unchanged.

**get\_refcell\_position()**

Get reference cell DC position between 0 and 1

**set\_refcell\_position**(*value*)

Set reference cell DC position between 0 and 1

**get\_refcell\_waveform\_params()**

Get reference cell waveform parameters.

Return tuple (lower\_limit, upper\_limit, oversamp, mode). mode can be "none", "avg", "min", or "max".

**set\_refcell\_waveform\_params**(*lower\_limit=None, upper\_limit=None, oversamp=None, mode=None*)

Set reference cell waveform parameters.

Any parameters which are None remain unchanged. mode can be "none", "avg", "min", or "max". oversamp should be between 4 and 512.

**get\_scan\_status()**

Get scan status ("run" or "stop")

**set\_scan\_status**(*status='run'*)

Set scan status ("run" or "stop")

**wait\_scan**(*timeout=None*)

Wait until scan is stopped

**get\_scan\_position()**

Get scan position

**set\_scan\_position**(*value*)

Set scan position



**get\_scan\_params()**

Get scan parameters.

Return tuple (device, mode, lower\_limit, upper\_limit, rise\_speed, fall\_speed). device can be "none", "slow\_piezo", or "ref\_cell". mode is a tuple (falling, stop\_lower, stop\_upper).

**set\_scan\_params(device=None, mode=None, lower\_limit=None, upper\_limit=None, rise\_speed=None, fall\_speed=None)**

Set slow piezo lock control parameters.

device can be "none", "slow\_piezo", or "ref\_cell". mode is a tuple (falling, stop\_lower, stop\_upper). Any parameters which are None remain unchanged.

**BackendError**

alias of [DeviceBackendError](#)

**apply\_settings(settings)**

Apply the settings.

settings is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If one\_line==True, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

include specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting include=-10 queries all available variables, which is equivalent to include="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

include specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting include=-10 queries all available variables, which is equivalent to include="all".

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

include specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting include=-10 queries all available variables, which is equivalent to include="all".

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset()**

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer()**

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**pylablib.devices.Sirah.base module****exception** pylablib.devices.Sirah.base.**GenericSirahError**Bases: *DeviceError*

Generic Sirah error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Sirah.base.**GenericSirahBackendError**(*exc*)Bases: *GenericSirahError*, *DeviceBackendError*

Sirah backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.devices.Sirah.tuner module****exception** pylablib.devices.Sirah.tuner.**FrequencyReadSirahError**(*timeout=None*)Bases: *GenericSirahError*

Sirah error indicating an error while trying to read frequency value

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Sirah.tuner.**MatisseTuner**(*laser, wavemeter, calibration=None, ref\_cell=True*)Bases: *object*

Matisse tuner.

Helps to coordinate with an external wavemeter to perform more complicated tasks: motors calibration, fine frequency tuning, and stitching scans.

**Parameters**

- **laser** – opened Matisse laser object
- **wavemeter** – opened wavemeter object (currently only HighFinesse wavemeters are supported)
- **calibration** – either a calibration dictionary, or a path to the calibration dictionary file

**set\_tune\_units**(*units='int'*)

Set default units for fine tuning and sweeping (fine sweep or stitched scan).

Can be either "int" (internal units between 0 and 1) or "freq" (frequency units; requires calibration).

**apply\_calibration**(*calibration*)

Apply the given calibration.

*calibration* is either a calibration dictionary, or a path to the calibration dictionary file. Contains information about the relation between bifi motor and wavelength, thin etalon motor span, slow piezo tuning rate (frequency to internal units) and its maximal sweep rate, ref cell tuning rate (frequency to internal units) and its maximal sweep rate.

**get\_frequency**(*timeout=1.0*)

Get current frequency reading.

The only method relying on the wavemeter. Can be extended or overloaded to support different wavemeters.

**get\_last\_read\_frequency**(*max\_delay=1.0*)

Get the last valid read frequency, or None if none has been acquired yet

**set\_frequency\_average\_time**(*avg\_time=0*)

Set averaging time for frequency measurements (reduces measured frequency jitter)

**scan\_steps**(*motor, start, stop, step*)

Scan the given motor ("bifi" or "thinet") in discrete steps within the given range with a given step.

Return a 4-column numpy array containing motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**scan\_centered**(*motor, span, step*)

Scan the given motor ("bifi" or "thinet") in discrete steps in a given span around the current position.

After the scan, return the motor to the original position.

Return a 4-column numpy array containing motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**scan\_quick**(*motor, start, stop, autmdir=True*)

Do a quick continuous scan of the given motor ("bifi" or "thinet") within the given range.

Compared to [scan\\_steps\(\)](#), which does a series of discrete defined moves, this method does a single continuous move and records values in its progress. This is quicker, but does not allow for the step size control, and results in non-uniform recorded positions. If *autmdir==False*, first initialize the motor to *start* and then move to *stop*; otherwise, initialize to whichever border is closer.

Return a 4-column numpy array containing motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**scan\_quick\_centered**(*motor, span*)

Do a quick continuous scan of the given motor ("bifi" or "thinet") in a given span around the current position.

After the scan, return the motor to the original position.

Return a 4-column numpy array containing motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**scan\_both\_motors**(*bifi\_rng*, *te\_rng*, *verbose=False*)

Perform a 2D grid scan changing positions of both birefringent filter and thin etalon motors.

*bifi\_rng* and *te\_rng* are both 3-tuples (*start*, *stop*, *step*) specifying the scan ranges. If *verbose==True*, print a message per every birefringent filter position indicating the scan progress.

Return a 5-column numpy array containing birefringent filter motor position, thin etalon motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**scan\_both\_motors\_quick**(*bifi\_rng*, *te\_rng*, *verbose=False*)

Perform a quick 2D grid scan changing positions of both birefringent filter and thin etalon motors.

For each discrete position of a birefringent filter motor perform a quick scan of the thin etalon motor. *bifi\_rng* is a 3-tuple (*start*, *stop*, *step*), while *te\_rng* is a 2-tuple (*start*, *stop*) specifying the scan ranges. If *verbose==True*, print a message per every birefringent filter position indicating the scan progress.

Return a 5-column numpy array containing birefringent filter motor position, thin etalon motor position, internal diode power, thin etalon reflection power, and wavemeter frequency.

**calibrate**(*motors=True*, *slow\_piezo=True*, *slow\_piezo\_speeds=None*, *ref\_cell=True*, *ref\_cell\_speeds=None*, *verbose=True*, *bifi\_range=None*, *thinet\_range=None*, *return\_scans=True*)

Calibrate the laser and return the calibration results.

If *motors==True*, perform motors calibration (*bifi* range and wavelengths, thin etalon range). If *slow\_piezo==True*, perform slow piezo calibration (ratio between internal tuning units and frequency shift). If *slow\_piezo\_speeds* is not *None*, it defines a list of slow piezo tuning speeds to use for the calibration (in case it depends on the speed). If *ref\_cell==True*, perform ref cell calibration (ratio between internal tuning units and frequency shift). If *ref\_cell\_speeds* is not *None*, it defines a list of ref cell tuning speeds to use for the calibration (in case it depends on the speed). If *bifi\_range* is specified, it is a tuple (*start*, *stop*, *step*) defining the tested *bifi* positions (default is between 100000 and 400000 with a step of 400). If *thinet\_range* is specified, it is a tuple (*start*, *stop*) defining the tested thin etalon position range. If *verbose==True*, print the progress updates during scan. If *return\_scans==True*, return a tuple (*calibration*, *scans*), where *scans* is a tuple (*motor\_scan*, *slow\_piezo\_scan*, *ref\_cell*) containing detail scan result tables; otherwise, return just the calibration dictionary.

**unlock\_all**()

Unlock all relevant locks (slow piezo, fast piezo, piezo etalon, thin etalon)

**set\_fine\_lock**(*device='slow\_piezo'*)

Set fine lock (slow and fast piezo) parameters for the given device ("low\_piezo" or "ref\_cell")

**fine\_tune\_to\_gen**(*target*, *device='slow\_piezo'*, *method='auto'*, *tolerance=None*)

Same as [fine\\_tune\\_to\(\)](#), but made as a generator which yields occasionally.

Can be used to run this scan in parallel with some other task, or to be able to interrupt it in the middle.

**fine\_tune\_to**(*target*, *device='slow\_piezo'*, *method='auto'*, *tolerance=None*)

Fine tune the laser to the given target frequency using only fine tuning.

*device* specifies the device used for fine tuning: either "slow\_piezo", or "ref\_cell". *method* can be "step" for step-based binary search method, or "cal" for slope-based method using the fine tuning calibration (frequency detuning per element position shift). (generally faster, but requires a known calibration). If *method=="auto"*, use "cal" when the calibration is available and "step" otherwise. *tolerance* gives the final frequency tolerance for the "cal" tuning method; if *None*, use the standard value (50MHz by default).

**tune\_to\_gen**(*target*, *level*='full', *fine\_device*='slow\_piezo', *tolerance*=None, *local\_level*='none')

Same as [tune\\_to\(\)](#), but made as a generator which yields occasionally.

Can be used to run this scan in parallel with some other task, or to be able to interrupt it in the middle.

**tune\_to**(*target*, *level*='full', *fine\_device*='slow\_piezo', *tolerance*=None, *local\_level*='none')

Tune the laser to the given frequency (in Hz) using multiple elements (bifi, thin etalon, piezo etalon, slow piezo / ref cell).

*level* can be "bifi" (only tune the bifi motor), "thin" (tune bifi motor and thin etalon), or "full" (full tuning using all elements). *fine\_device* specifies the device used for fine tuning: either "slow\_piezo", or "ref\_cell". *tolerance* gives the final fine tuning frequency tolerance; if None, use the standard value (50MHz by default). *local\_level* defines the level on which to start adjustment; can be "fine" (start with the slow piezo or the ref cell, if the laser is within their tuning range), "thin" (start with the thin etalon), or "none" (start with the bifi; default). If using just the finer control does not work, progressively move to the coarser ones.

**fine\_sweep\_start**(*span*, *up\_speed*, *down\_speed*=None, *device*='slow\_piezo', *kind*='cont\_up', *current\_pos*=0.5)

Start a fine sweep using the slow piezo or the ref cell.

*span* is a sweep span, *up\_speed* and *down\_speed* are the corresponding speeds (if *down\_speed* is None, use the same as *up\_speed*), *device* is the scan device ("slow\_piezo" or "ref\_cell"), *kind* is the sweep kind ("cont\_up", "cont\_down", "single\_up", or "single\_down"), and *current\_pos* is the relative position of the current position within the sweep range (0 means that it's the lowest position of the sweep, 1 means it's the highest, 0.5 means that it's in the center).

**fine\_sweep\_stop**(*return\_to\_start*=True, *start\_point*=None)

Stop currently running fast sweep.

If *return\_to\_start*==True, return to the original start tuning position after the sweeps is stopped; otherwise, stay at the current position.

**scan\_coarse\_gen**(*bifi\_rng*, *te\_rng*)

Perform a 2D grid scan changing positions of both birefringent filter and thin etalon motors.

*bifi\_rng* and *te\_rng* are both 3-tuples (start, stop, step) specifying the scan ranges.

Yields a tuple ((*bifi\_idx*, *bifi\_npos*), (*te\_idx*, *te\_npos*)), where *bifi\_idx* and *te\_idx* are the indices of the current birefringent filter and thin etalon motor positions, and *bifi\_npos* and *te\_npos* are the corresponding total numbers of positions.

**stitched\_scan\_gen**(*full\_rng*, *single\_span*, *speed*, *device*='slow\_piezo', *overlap*=0.1, *freq\_step*=None, *segment\_end\_timeout*=None)

Same as [stitched\\_scan\(\)](#), but made as a generator which yields occasionally.

Can be used to run this scan in parallel with some other task, or to be able to interrupt it in the middle. Yields True whenever the main scanning region is passing, and False during the stitching intervals.

**stitched\_scan**(*full\_rng*, *single\_span*, *speed*, *device*='slow\_piezo', *overlap*=0.1, *freq\_step*=None, *segment\_end\_timeout*=None)

Perform a stitched laser scan.

#### Parameters

- **full\_rng** – 2-tuple (start, stop) with the full frequency scan range.
- **single\_span** – magnitude of a single continuous scan segment given in the slow piezo scan units (between 0 and 1)
- **speed** – single segment scan speed

- **device** – the scan device ("slow\_piezo" or "ref\_cell")
- **overlap** – overlap of consecutive segments, as a fraction of *single\_span*
- **freq\_step** – if None, the start of the next segment is calculated based on the end of the previous segment and *overlap*; otherwise, it specifies a fixed frequency step between segments.

## Module contents

### pylablib.devices.SmarAct package

#### Submodules

#### pylablib.devices.SmarAct.MCS2 module

**class** pylablib.devices.SmarAct.MCS2.**LibraryController**(*lib*)

Bases: *LibraryController*

**close**(*opid*)

Mark device closing.

Return tuple (close\_result, uninit\_result) with the results of the closing and the shutdown. If library does not need to be shut down yet, set uninit\_result=None

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (init\_result, open\_result, opid) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set init\_result=None

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

pylablib.devices.SmarAct.MCS2.**list\_devices**()

List all connected SmarAct MCS2 devices

pylablib.devices.SmarAct.MCS2.**get\_devices\_number**()

Get number of connected SmarAct MCS2 controller

pylablib.devices.SmarAct.MCS2.**get\_SDK\_version**()

Get version of MCS2 SDK

**class** pylablib.devices.SmarAct.MCS2.**TDeviceInfo**(*serial, name*)

Bases: *tuple*



**name****serial**

```
class pylablib.devices.SmarAct.MCS2.TCLMoveParams(velocity, acceleration, max_step_frequency,  
                                                hold_time)
```

Bases: `tuple`**acceleration****hold\_time****max\_step\_frequency****velocity**

```
class pylablib.devices.SmarAct.MCS2.TStepMoveParams(frequency, amplitude)
```

Bases: `tuple`**amplitude****frequency**

```
class pylablib.devices.SmarAct.MCS2.TScanMoveParams(velocity)
```

Bases: `tuple`**velocity**

```
class pylablib.devices.SmarAct.MCS2.MCS2(locator)
```

Bases: `IMultiaxisStage`

SmarAct MCS2 translation stage controller.

**Parameters****locator** (`str`) – controller locator (returned by `get_devices_number()` function)**Error**alias of `SmarActError`**open()**

Open the connection to the stage

**close()**

Close the connection to the stage

**is\_opened()**

Check if the device is connected

**get\_property(name, idx=0)**

Get stage property with the given name and index

**get\_all\_properties(scope='all', idx='all')**

Get all controller properties within the given scope and for the given index.

*scope* can be "dev" (device properties), "mod" (module properties), "cha" (channel properties), or "api" (api properties); it can also be a list of several scopes, or "all", which includes all properties. *idx* is the index and usually applies to "cha" or "mod" scopes; for other scopes it should be set to 0 or "all".

**set\_property(name, value, idx=0)**

Set stage property with the given name and index

**get\_device\_info()**

Get the device info of the controller board.

Return tuple (serial, name).

**get\_default\_axis()**

Get the default axis (the one automatically applied to channel-related methods)

**set\_default\_axis(axis)**

Set the default axis (the one automatically applied to channel-related methods).

Can be a zero-based axis index or "all"

**using\_default\_axis(axis)**

Context manager for temporarily changing the default axis

**get\_status\_n(axis=None)**

Get axis status as an integer

**get\_status(axis=None)**

Get axis status as a set of string descriptors

**is\_moving(axis=None)**

Check if a given axis is moving (including referencing and calibrating)

**wait\_move(axis, timeout=30.0)**

Wait for a given axis to stop moving

**get\_device\_status\_n()**

Get device status as an integer

**get\_device\_status()**

Get axis status as a set of string descriptors

**get\_module\_status\_n(index=0)**

Get module status as an integer

**get\_module\_status(index)**

Get module status as a set of string descriptors

**get\_cl\_move\_parameters(axis=None)**

Get closed-loop move parameters.

Return tuple (velocity, acceleration, max\_step\_frequency, hold\_time) with the maximal move velocity (in m/s or deg/s), move acceleration (in m/s<sup>2</sup> or deg/s<sup>2</sup>), maximal step frequency (in Hz), and position hold time (in s, or "inf" if it is infinite)

**setup\_cl\_move(velocity=None, acceleration=None, max\_step\_frequency=None, hold\_time=None, axis=None)**

Set closed-loop move parameters.

For the meaning of the parameters, see [get\\_cl\\_move\\_parameters\(\)](#). Note that changing the hold time will only apply after the next move command. To apply it without actual moving, you can call [move\\_by\(\)](#) method with distance=0 for the appropriate axis. If any parameter is None, use the current value.

**get\_step\_move\_parameters(axis=None)**

Get step move parameters.

Return tuple (frequency, amplitude) with the step frequency (in Hz) and step amplitude (normalized between 0 and 1).

**setup\_step\_move**(*frequency=None, amplitude=None, axis=None*)

Set step move parameters.

For the meaning of the parameters, see [get\\_step\\_move\\_parameters\(\)](#). If any parameter is *None*, use the current value.

**get\_scan\_move\_parameters**(*axis=None*)

Get scan move parameters.

Return tuple (*velocity*) with the move velocity (amplitude per second; amplitude is normalized between 0 and 1).

**setup\_scan\_move**(*velocity=None, axis=None*)

Set scan move parameters.

For the meaning of the parameters, see [get\\_scan\\_move\\_parameters\(\)](#). If any parameter is *None*, use the current value.

**get\_range\_limit**(*axis=None*)

Get the movement range limit (in m or deg) for the given axis.

Return (*min*, *max*) if the limit is active or *None* otherwise.

**set\_range\_limit**(*limit, axis=None*)

Set the movement range limit (in m or deg) for the given axis.

*limit* is either a tuple (*min*, *max*) if the limit is active, or *None* otherwise.

**get\_position**(*axis=None*)

Get current position (in m or deg) at the given axis

**set\_position\_reference**(*position=0, axis=None*)

Get the current position (in m or deg) at the given axis.

This method simply shifts the position sensor reference; the stage does not move.

**get\_scan\_position**(*axis=None*)

Get current scan position (piezo voltage; normalized between 0 and 1) at the given axis

**get\_target\_position**(*axis=None*)

Get current target position (in m or deg) at the given axis

**move\_to**(*position, axis=None*)

Move to the given position (in m or deg) at the given axis

**move\_by**(*distance, axis=None*)

Move by the given distance (in m or deg) at the given axis

**move\_by\_steps**(*steps, axis=None*)

Move by the given number of steps at the given axis

**move\_scan\_to**(*position, axis=None*)

Move to the given open-loop position (piezo voltage; normalized between 0 and 1) using just a piezo deflection at the given axis

**move\_scan\_by**(*distance, axis=None*)

Move by the given open-loop distance (piezo voltage; normalized between -1 and 1) using just a piezo deflection at the given axis

**stop**(*axis=None*)

Stop motion at the given axis

**home**(*axis=None, sync=True, start\_direction='+', reverse\_direction=False, abort\_on\_stop=False, auto\_zero=False, continue\_on\_found=False, stop\_on\_found=False*)

Home (reference) the given axis.

If `sync==True`, wait until the homing is done. The other parameters are flags setting up the referencing behavior. See MCS2 programming manual section on reference marks for the details.

**calibrate**(*axis=None, sync=True, direction='+', detect\_code\_inversion=False, advanced\_sensor\_correction=False, limited\_stage\_range=False*)

Calibrate the given axis.

If `sync==True`, wait until the calibration is done. The other parameters are flags setting up the calibration behavior. See MCS2 programming manual section on calibrating for the details.

**lowlevel\_move**(*value, axis=None*)

Execute the low-level movement command with the given integer value.

The meaning of the value depends on the devices properties (see MCS2 programming manual for the details). This is a low-level method, whose high-level functionality is covered by other move methods.

**lowlevel\_reference**(*axis=None*)

Execute the low-level reference command with the given integer value.

Exact procedure depends on the devices properties (see MCS2 programming manual for the details). This is a low-level method, whose high-level functionality is covered by the [home\(\)](#) method.

**lowlevel\_calibrate**(*axis=None*)

Execute the low-level calibration command with the given integer value.

Exact procedure depends on the devices properties (see MCS2 programming manual for the details). This is a low-level method, whose high-level functionality is covered by the [calibrate\(\)](#) method.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {**name**: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {**name**: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {**name**: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings(*include=0*)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**remap\_axes(*mapping, accept\_original=True*)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_variable(*key, value*)**

Set the value of a settings parameter

**pylablib.devices.SmarAct.base module****exception pylablib.devices.SmarAct.base.SmarActError**

Bases: [DeviceError](#)

Generic SmarAct error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.devices.SmarAct.scu3d module****class pylablib.devices.SmarAct.scu3d.LibraryController(*lib*)**

Bases: [LibraryController](#)

**close(*opid*)**

Mark device closing.

Return tuple (close\_result, uninit\_result) with the results of the closing and the shutdown. If library does not need to be shut down yet, set uninit\_result=None

**get\_opened\_num()**

Get number of opened devices

**open()**

Mark device opening.

Return tuple (init\_result, open\_result, opid) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set init\_result=None

**preinit()**

Pre-initialize the library, if it hasn't been done already

**shutdown()**

Close all opened connections and shutdown the library

**temp\_open()**

Context for temporarily opening a new device connection

**class** pylablib.devices.SmarAct.scu3d.**TDeviceInfo**(*device\_id, firmware\_version, dll\_version*)

Bases: [tuple](#)

**device\_id**

**dll\_version**

**firmware\_version**

pylablib.devices.SmarAct.scu3d.**get\_device\_info**(*idx*)

Get info of the devices with the given index.

Return tuple (device\_id, firmware\_version, dll\_version).

pylablib.devices.SmarAct.scu3d.**list\_devices**()

List all connected devices

pylablib.devices.SmarAct.scu3d.**get\_devices\_number**()

Get number of connected SCU3D controller

**class** pylablib.devices.SmarAct.scu3d.**SCU3D**(*idx=0, axis\_dir='+++'*)

Bases: [IMultiaxisStage](#)

SmarAct SCU3D translation stage controller.

#### Parameters

- **idx** (*int*) – stage index
- **axis\_dir** (*str*) – 3-symbol string specifying default directions of the axes (each symbol be "+" or "-")

**Error** = <Mock name='mock.SmarActError' id='140527551158928'>

**open()**

Open the connection to the stage

**close()**

Close the connection to the stage

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get info of the devices with the given index.

Return tuple (device\_id, firmware\_version, dll\_version).

**get\_axis\_dir()**

Get axis direction convention (a string of 3 symbols which are either "+" or "-" determining if the axis direction is flipped)

**set\_axis\_dir**(*axis\_dir*)

Set axis direction convention (a string of 3 symbols which are either "+" or "-" determining if the axis direction is flipped)

**move\_macrostep**(*axis, steps, voltage, frequency*)

Move along a given axis by a single “macrostep”, which consists of several regular steps.

*voltage* (in Volts) and *frequency* (in Hz) specify the motion parameters. This simulates the controller operation, where one “step” at large step sizes consists of several small steps.

**move\_by**(*axis, steps=1, stepsize=10*)

Move along a given axis with a given number of macrosteps using one of the predefined step size.

*stepsize* can range from 1 (smallest) to 20 (largest), and roughly corresponds to the handheld controller parameters.

**get\_status**(*axis='all'*)

Get the axis status.

Can be "stopped" (default state), "setting\_amplitude" (setting open-loop step amplitude), "moving" (open-loop movement), "targeting" (closed-loop movement), "holding" (closed-loop position holding), "calibrating" (sensor calibration), or "moving\_to\_reference" (calibrating position sensor).

**wait\_for\_status**(*axis, status='stopped', timeout=30.0*)

Wait until the axis reaches a given status.

By default wait for "stopped" status (i.e., wait until the motion is finished).

**wait\_move**(*axis, timeout=30.0*)

Wait for a given axis to stop moving

**is\_moving**(*axis='all'*)

Check if a given axis is moving

**stop**(*axis='all'*)

Stop motion at a given axis

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**remap\_axes**(*mapping, accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by *get\_all\_axes()*), or a dictionary {alias: original} of the new axes aliases.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

## Module contents

### pylablib.devices.Standa package

#### Submodules

#### pylablib.devices.Standa.base module

**exception** pylablib.devices.Standa.base.StandaError

Bases: *DeviceError*

Generic Standa device StandaError

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Standa.base.StandaBackendError(*exc*)

Bases: *StandaError, DeviceBackendError*

Generic Standa backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Standa.base.TEngineType(*engine, driver*)

Bases: *tuple*

**driver**

**engine**



```
class pylablib.devices.Standa.base.TStepperMotorCalibration(steps_per_rev, usteps_per_step)
```

```
    Bases: tuple
```

```
    steps_per_rev
```

```
    usteps_per_step
```

```
class pylablib.devices.Standa.base.TFullState(smov, scmd, spwr, senc, swnd, position, encoder, speed,  
                                              ivpwr, ivusb, temp, flags, gpio)
```

```
    Bases: tuple
```

```
    encoder
```

```
    flags
```

```
    gpio
```

```
    ivpwr
```

```
    ivusb
```

```
    position
```

```
    scmd
```

```
    senc
```

```
    smov
```

```
    speed
```

```
    spwr
```

```
    swnd
```

```
    temp
```

```
class pylablib.devices.Standa.base.TMoveParams(speed, accel, decel, antiplay)
```

```
    Bases: tuple
```

```
    accel
```

```
    antiplay
```

```
    decel
```

```
    speed
```

```
class pylablib.devices.Standa.base.TPowerParams(hold_current, reduct_enabled, reduct_delay,  
                                              off_enabled, off_delay, ramp_enabled, ramp_time)
```

```
    Bases: tuple
```

```
    hold_current
```

```
    off_delay
```

```
    off_enabled
```

```
    ramp_enabled
```

**ramp\_time**

**reduct\_delay**

**reduct\_enabled**

**class** `pylablib.devices.Standa.base.Standa8SMC(conn)`

Bases: *ICommBackendWrapper*, *IStage*

Generic Standa 8SMC4/8SMC5 controller device.

**Parameters**

**conn** – serial connection parameters (usually port, a tuple containing port and baudrate, or a tuple with full specification such as ("COM1", 115200, 8, 'N', 2))

**Error**

alias of *StandaError*

**query**(*cmd*, *data=b"*, *retlen=None*)

**pquery**(*cmd*, *\*args*)

**get\_engine\_type**()

Get engine and driver type

**get\_stepper\_motor\_calibration**()

Get stepper motor calibration parameters.

Return tuple (steps\_per\_rev, usteps\_per\_step).

**get\_status**()

Get device status.

Return tuple (smov, scmd, spwr, senc, swnd, position, encoder, speed, ivpwr, ivusb, temp, flags, gpio) with the moving state (whether motor is moving, reached speed, etc.), command state (last issued command and its status), power state, encoder state, winding state (currently not used), step position, encoder position, current speed, current and voltage of the power supply, current and voltage of the USB source, temperature (in C), and additional state and GPIO flags.

**is\_moving**()

Check if the motor is moving

**wait\_move**(*timeout=None*)

Wait until motion is done

**get\_position**()

Return step position (in steps for a DC motor, in microsteps for a stepper motor)

**get\_encoder**()

Return encoder position

**set\_position\_reference**(*position=0*)

Set position reference (in steps for a DC motor, in microsteps for a stepper motor).

Actual motor position stays the same.

**set\_encoder\_reference**(*position=0*)

Set encoder reference.

Actual motor position stays the same.

**move\_to**(*position*)

Move to the given position (in steps for a DC motor, in microsteps for a stepper motor)

**move\_by**(*distance*)

Move by the given distance (in steps for a DC motor, in microsteps for a stepper motor)

**stop**(*immediate=False*)

**power\_off**(*stop='soft'*)

**jog**(*direction*)

Start moving in a given direction ("+" or "-")

**home**(*sync=True, timeout=30.0*)

Home the motor.

If *sync==True*, wait until the homing is complete, or until *timeout* expires.

**get\_move\_parameters**()

Get moving parameters.

Return tuple (*speed*, *accel*, *decel*, *antiplay*).

**setup\_move**(*speed=None, accel=None, decel=None, antiplay=None*)

Setup moving parameters.

If any parameter is *None*, use the current value.

**get\_power\_parameters**()

Get power parameters.

Return tuple (*hold\_current*, *reduct\_enabled*, *reduct\_delay*, *off\_enabled*, *off\_delay*, *ramp\_enabled*, *ramp\_time*).

**setup\_power**(*hold\_current=None, reduct\_enabled=None, reduct\_delay=None, off\_enabled=None, off\_delay=None, ramp\_enabled=None, ramp\_time=None*)

Setup power parameters.

If any parameter is *None*, use the current value.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Tektronix package

#### Submodules

#### pylablib.devices.Tektronix.base module

**exception** pylablib.devices.Tektronix.base.TektronixError

Bases: *DeviceError*

Generic Tektronix devices error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Tektronix.base.TektronixBackendError`(*exc*)

Bases: `TektronixError`, `DeviceBackendError`

Generic Tektronix backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

`pylablib.devices.Tektronix.base.muxchannel`(\*args, \*\*kwargs)

Multiplex the function over its channel argument

**class** `pylablib.devices.Tektronix.base.TTriggerParameters`(*source, level, coupling, slope*)

Bases: `tuple`

**coupling**

**level**

**slope**

**source**

**class** `pylablib.devices.Tektronix.base.ITektronixScope`(*addr, nchannels='auto'*)

Bases: `SCPIDevice`

Generic Tektronix oscilloscope.

**Parameters**

- **addr** – device address; usually a VISA address string such as "USB0::0x0699::0x0364::C0000000::INSTR"
- **nchannels** – can specify number of channels on the oscilloscope; by default, autodetect number of channels (might take several seconds on connection)

**Error**

alias of `TektronixError`

**ReraiseError**

alias of `TektronixBackendError`

**get\_channels\_number**()

Get the number of channels

**get\_channels**(*only\_main=False*)

Get the list of all input channels (if *only\_main==True*) or all available channels (if *only\_main==False*)

**normalize\_channel\_name**(*channel*)

Normalize channel name as represented by the oscilloscope

**grab\_single**(*wait=True, software\_trigger=False, wait\_timeout=None*)

Set single waveform grabbing and wait for acquisition.

If *wait==True*, wait until the acquisition is complete; otherwise, return immediately. if *software\_trigger==True*, send the software trigger after setup (i.e., the device triggers immediately regardless of the input).

**wait\_for\_grabbing**(*timeout=None*)

Wait until the acquisition is complete

**grab\_continuous**(*enable=True*)

Start or stop continuous grabbing

**stop\_grabbing**()

Stop grabbing or waiting (equivalent to `self.grab_continuous(False)`)

**is\_continuous**()

Check if grabbing is continuous or single

**is\_grabbing**()

Check if acquisition is in progress.

Return True if the oscilloscope is recording data, or if the trigger is armed/ready and waiting; return False if the acquisition is stopped. To check if the trigger has been triggered, use [`get\_trigger\_state\(\)`](#).

**get\_edge\_trigger\_source**()

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**set\_edge\_trigger\_source**(*channel*)

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**get\_edge\_trigger\_coupling**()

Get edge trigger coupling ("ac" or "dc")

**set\_edge\_trigger\_coupling**(*coupling*)

Set edge trigger coupling ("ac" or "dc")

**get\_edge\_trigger\_slope**()

Get edge trigger slope ("fall" or "rise")

**set\_edge\_trigger\_slope**(*slope*)

Set edge trigger slope ("fall" or "rise")

**get\_trigger\_level**()

Get edge trigger level (in Volts)

**set\_trigger\_level**(*level*)

Set edge trigger level (in Volts)

**setup\_edge\_trigger**(*source, level, coupling='dc', slope='rise'*)

Setup edge trigger.

Set source, level, coupling and slope (see corresponding methods for details).

**get\_trigger\_mode**()

Get trigger mode.

Can be either "auto" or "norm".

**set\_trigger\_mode**(*trigger\_mode='auto'*)

Set trigger mode.

Can be either "auto" or "norm".

**get\_trigger\_state()**

Get trigger state.

Can be "armed" (acquiring pretrigger), "ready" (pretrigger acquired, wait for trigger event), "trigger" (triggered, acquiring the rest of the waveform), "auto" ("auto" mode trigger is acquiring data in the absence of trigger), "save" (acquisition is stopped), or "scan" (oscilloscope in the scan mode)

**force\_trigger()**

Force trigger event

**get\_horizontal\_span()**

Get horizontal span (in seconds)

**set\_horizontal\_span(*span*)**

Set horizontal span (in seconds)

**get\_horizontal\_offset()**

Get horizontal offset (position of the center of the sweep; in seconds)

**set\_horizontal\_offset(*offset=0.0*)**

Set horizontal offset (position of the center of the sweep; in seconds)

**get\_vertical\_span(*channel*)**

Get channel vertical span (in V)

**set\_vertical\_span(*channel, span*)**

Set channel vertical span (in V)

**get\_vertical\_position(*channel*)**

Get channel vertical position (offset of the zero volt line; in V)

**set\_vertical\_position(*channel, position*)**

Set channel vertical position (offset of the zero volt line; in V)

**is\_channel\_enabled(*channel*)**

Check if channel is enabled

**enable\_channel(*channel, enabled=True*)**

Enable or disable given channel

**get\_selected\_channel()**

Get selected source channel.

Return number if it is a real channel, or a string name otherwise.

**select\_channel(*channel*)**

Select a channel to read data.

Doesn't need to be called explicitly, if [read\\_multiple\\_sweeps\(\)](#) or [read\\_sweep\(\)](#) are used.

**get\_coupling(*channel*)**

Get channel coupling.

Can be "ac", "dc", or "gnd".

**set\_coupling(*channel, coupling='dc'*)**

Set channel coupling.

Can be "ac", "dc", or "gnd".

**get\_probe\_attenuation**(*channel*)

Get channel probe attenuation

**set\_probe\_attenuation**(*channel*, *attenuation*)

Set channel probe attenuation

**get\_points\_number**(*kind*='send')

Get number of datapoints in various context.

*kind* defines the context. It can be "acq" (number of points acquired), "trace" (number of points in the source of the read-out trace; can be lower than "acq" if the data resolution is reduced, or if the source is not a channel data), or "send" (number of points in the sent waveform; can be lower than "trace" if [get\\_data\\_pts\\_range\(\)](#) is used to specify and incomplete range). Not all kinds are defined for all scope model (e.g., "trace" is not defined for TDS2000 series oscilloscopes).

For length of read-out trace, see also [get\\_data\\_pts\\_range\(\)](#).

**set\_points\_number**(*pts\_num*, *reset\_limits*=True)

Set number of datapoints to record when acquiring a trace.

If *reset\_limits*==True, reset the datapoints range ([set\\_data\\_pts\\_range\(\)](#)) to the full range. The actual set value (returned by this method) can be different from the requested value.

**get\_data\_pts\_range**()

Get range of data points to read.

The range is defined from 1 to the points number (returned by [get\\_points\\_number\(\)](#)).

**set\_data\_pts\_range**(*rng*=None)

Set range of data points to read.

The range is defined from 1 to the points number (returned by [get\\_points\\_number\(\)](#) with *kind*="acq"). If *rng* is None, set the full range.

**set\_data\_format**(*fmt*='default')

Set data transfer format.

*fmt* is a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2"). If "default", use the oscilloscope default format (usually binary with smallest appropriate byte size).

**get\_data\_format**()

Get data transfer format.

Return a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2").

**get\_wfmpre**(*channel*=None, *enable*=True)

Get preamble dictionary describing all scaling and format data for the given channel or a list of channels.

Can be acquired once and used in subsequent multiple reads to save time on re-requesting. If *channel* is None, use the currently selected channel. If *enable*==True, make sure that the requested channel is enabled; getting preamble for disabled channels raises an error.

**read\_raw\_data**(*channel*=None, *fmt*=None, *timeout*=None)

Request, read and parse raw data at a given channel.

*fmt* is data format (e.g., "i1", "<i2", or "ascii") or "default", which uses the default oscilloscope format (usually binary with smallest appropriate byte size). If *fmt* is None, use the current format. If *channel* is None, use the currently selected channel.

Returned data is raw (i.e., not scaled and without x axis).



**read\_multiple\_sweeps**(*channels*, *wfmpres=None*, *ensure\_fmt=False*, *timeout=None*,  
*return\_wfmpres=None*)

Read data from a multiple channels channel.

#### Parameters

- **channels** – list of channel indices or names
- **wfmpres** – optional list or dictionary of preambles (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout
- **return\_wfmpres** – if *True*, return tuple (*sweeps*, *wfmpres*), where *wfmpres* can be used for further sweep readouts.

**read\_sweep**(*channel*, *wfmpre=None*, *ensure\_fmt=True*, *timeout=None*)

Read data from a single channel.

#### Parameters

- **channel** – channel index or name
- **wfmpre** – optional preamble dictionary (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout

#### BackendError

alias of [DeviceBackendError](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type='string'*, *delay=0.0*, *timeout=None*, *read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive *write()* operations are bundled together with ; delimiter. The actual write is performed at the *read()/ask()* operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform *wait\_sync()*), 'dev' (perform *wait\_dev()*) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".

- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ",".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.Tektronix.base.TDS2000(addr, nchannels='auto')`

Bases: *ITektronixScope*

Tektronix TDS2000 series oscilloscope.

#### Parameters

- **addr** – device address; usually a VISA address string such as `"USB0::0x0699::0x0364::C0000000::INSTR"`
- **nchannels** – can specify number of channels on the oscilloscope; by default, autodetect number of channels (might take several seconds on connection)

#### BackendError

alias of *DeviceBackendError*

#### Error

alias of *TektronixError*

#### ReraiseError

alias of *TektronixBackendError*

#### **apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

#### **ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in `read()`. If `read_echo==True`, assume that the device first echoes the input and skip it.

#### **close**()

Close the backend

#### **enable\_channel**(*channel*, *enabled*=True)

Enable or disable given channel

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**force\_trigger**()

Force trigger event

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_channels**(*only\_main=False*)

Get the list of all input channels (if *only\_main==True*) or all available channels (if *only\_main==False*)

**get\_channels\_number**()

Get the number of channels

**get\_coupling**(*channel*)

Get channel coupling.

Can be "ac", "dc", or "gnd".

**get\_data\_format**()

Get data transfer format.

Return a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2").

**get\_data\_pts\_range**()

Get range of data points to read.

The range is defined from 1 to the points number (returned by [get\\_points\\_number\(\)](#)).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_edge\_trigger\_coupling**()

Get edge trigger coupling ("ac" or "dc")

**get\_edge\_trigger\_slope**()

Get edge trigger slope ("fall" or "rise")

**get\_edge\_trigger\_source**()

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_horizontal\_offset()**

Get horizontal offset (position of the center of the sweep; in seconds)

**get\_horizontal\_span()**

Get horizontal span (in seconds)

**get\_id(*timeout=None*)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_points\_number(*kind='send'*)**

Get number of datapoints in various context.

*kind* defines the context. It can be "acq" (number of points acquired), "trace" (number of points in the source of the read-out trace; can be lower than "acq" if the data resolution is reduced, or if the source is not a channel data), or "send" (number of points in the sent waveform; can be lower than "trace" if [get\\_data\\_pts\\_range\(\)](#) is used to specify and incomplete range). Not all kinds are defined for all scope model (e.g., "trace" is not defined for TDS2000 series oscilloscopes).

For length of read-out trace, see also [get\\_data\\_pts\\_range\(\)](#).

**get\_probe\_attenuation(*channel*)**

Get channel probe attenuation

**get\_selected\_channel()**

Get selected source channel.

Return number if it is a real channel, or a string name otherwise.

**get\_settings(*include=0*)**

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_level()**

Get edge trigger level (in Volts)

**get\_trigger\_mode()**

Get trigger mode.

Can be either "auto" or "norm".

**get\_trigger\_state()**

Get trigger state.

Can be "armed" (acquiring pretrigger), "ready" (pretrigger acquired, wait for trigger event), "trigger" (triggered, acquiring the rest of the waveform), "auto" ("auto" mode trigger is acquiring data in the absence of trigger), "save" (acquisition is stopped), or "scan" (oscilloscope in the scan mode)

**get\_vertical\_position(*channel*)**

Get channel vertical position (offset of the zero volt line; in V)

**get\_vertical\_span(*channel*)**

Get channel vertical span (in V)

**get\_wfmpre(*channel=None, enable=True*)**

Get preamble dictionary describing all scaling and format data for the given channel or a list of channels.

Can be acquired once and used in subsequent multiple reads to save time on re-requesting. If *channel* is *None*, use the currently selected channel. If *enable==True*, make sure that the requested channel is enabled; getting preamble for disabled channels raises an error.

**grab\_continuous**(*enable=True*)

Start or stop continuous grabbing

**grab\_single**(*wait=True, software\_trigger=False, wait\_timeout=None*)

Set single waveform grabbing and wait for acquisition.

If *wait==True*, wait until the acquisition is complete; otherwise, return immediately. if *software\_trigger==True*, send the software trigger after setup (i.e., the device triggers immediately regardless of the input).

**is\_channel\_enabled**(*channel*)

Check if channel is enabled

**is\_continuous**()

Check if grabbing is continuous or single

**is\_grabbing**()

Check if acquisition is in progress.

Return *True* if the oscilloscope is recording data, or if the trigger is armed/ready and waiting; return *False* if the acquisition is stopped. To check if the trigger has been triggered, use [get\\_trigger\\_state\(\)](#).

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**normalize\_channel\_name**(*channel*)

Normalize channel name as represented by the oscilloscope

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**read\_multiple\_sweeps**(*channels, wfmpres=None, ensure\_fmt=False, timeout=None, return\_wfmpres=None*)

Read data from a multiple channels channel.

#### Parameters

- **channels** – list of channel indices or names
- **wfmpres** – optional list or dictionary of preambles (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout
- **return\_wfmpres** – if *True*, return tuple (*sweeps*, *wfmpres*), where *wfmpres* can be used for further sweep readouts.

**read\_raw\_data**(*channel=None, fmt=None, timeout=None*)

Request, read and parse raw data at a given channel.

*fmt* is data format (e.g., "i1", "<i2", or "ascii") or "default", which uses the default oscilloscope format (usually binary with smallest appropriate byte size). If *fmt* is *None*, use the current format. If *channel* is *None*, use the currently selected channel.

Returned data is raw (i.e., not scaled and without x axis).

**read\_sweep**(*channel, wfmpre=None, ensure\_fmt=True, timeout=None*)

Read data from a single channel.

#### Parameters

- **channel** – channel index or name
- **wfmpre** – optional preamble dictionary (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset()**

Reset the device (by default, "\*RST" command)



**select\_channel**(*channel*)

Select a channel to read data.

Doesn't need to be called explicitly, if `read_multiple_sweeps()` or `read_sweep()` are used.

**set\_coupling**(*channel*, *coupling*='dc')

Set channel coupling.

Can be "ac", "dc", or "gnd".

**set\_data\_format**(*fmt*='default')

Set data transfer format.

*fmt* is a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2").

If "default", use the oscilloscope default format (usually binary with smallest appropriate byte size).

**set\_data\_pts\_range**(*rng*=None)

Set range of data points to read.

The range is defined from 1 to the points number (returned by `get_points_number()` with `kind="acq"`).

If *rng* is None, set the full range.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_edge\_trigger\_coupling**(*coupling*)

Set edge trigger coupling ("ac" or "dc")

**set\_edge\_trigger\_slope**(*slope*)

Set edge trigger slope ("fall" or "rise")

**set\_edge\_trigger\_source**(*channel*)

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**set\_horizontal\_offset**(*offset*=0.0)

Set horizontal offset (position of the center of the sweep; in seconds)

**set\_horizontal\_span**(*span*)

Set horizontal span (in seconds)

**set\_points\_number**(*pts\_num*, *reset\_limits*=True)

Set number of datapoints to record when acquiring a trace.

If `reset_limits==True`, reset the datapoints range (`set_data_pts_range()`) to the full range. The actual set value (returned by this method) can be different from the requested value.

**set\_probe\_attenuation**(*channel*, *attenuation*)

Set channel probe attenuation

**set\_trigger\_level**(*level*)

Set edge trigger level (in Volts)

**set\_trigger\_mode**(*trigger\_mode*='auto')

Set trigger mode.

Can be either "auto" or "norm".

**set\_vertical\_position**(*channel*, *position*)

Set channel vertical position (offset of the zero volt line; in V)

**set\_vertical\_span**(*channel*, *span*)

Set channel vertical span (in V)

**setup\_edge\_trigger**(*source*, *level*, *coupling*='dc', *slope*='rise')

Setup edge trigger.

Set source, level, coupling and slope (see corresponding methods for details).

**sleep**(*delay*)

Wait for *delay* seconds

**stop\_grabbing**()

Stop grabbing or waiting (equivalent to `self.grab_continuous(False)`)

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with ; delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type*='sync', *timeout*=None, *wait\_callback*=None)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_for\_grabbing**(*timeout*=None)

Wait until the acquisition is complete

**wait\_sync**(*timeout*=None, *wait\_callback*=None)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg*, *arg*=None, *arg\_type*=None, *unit*=None, *bool\_selector*=None, *wait\_sync*=None, *read\_echo*=False, *read\_echo\_delay*=0.0)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{: .3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".

- **unit** (*str*) – If not `None`, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (`false_value`, `true_value`) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if `True`, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (`False` by default).
- **read\_echo** (*bool*) – If `True`, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.Tektronix.base.DPO2000(addr, nchannels='auto')`

Bases: [`ITektronixScope`](#)

Tektronix DPO2000 series oscilloscope.

#### Parameters

- **addr** – device address; usually a VISA address string such as `"USB0::0x0699::0x0364::C0000000::INSTR"`
- **nchannels** – can specify number of channels on the oscilloscope; by default, autodetect number of channels (might take several seconds on connection)

#### BackendError

alias of [`DeviceBackendError`](#)

#### Error

alias of [`TektronixError`](#)

#### ReraiseError

alias of [`TektronixBackendError`](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {`name`: `value`} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [`read\(\)`](#). If `read_echo==True`, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**enable\_channel**(*channel*, *enabled*=True)

Enable or disable given channel

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If `one_line==True`, read only a single line.

**force\_trigger**()

Force trigger event

**static get\_arg\_type(*arg*)**

Autodetect argument type

**get\_channels(*only\_main=False*)**

Get the list of all input channels (if *only\_main==True*) or all available channels (if *only\_main==False*)

**get\_channels\_number()**

Get the number of channels

**get\_coupling(*channel*)**

Get channel coupling.

Can be "ac", "dc", or "gnd".

**get\_data\_format()**

Get data transfer format.

Return a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2").

**get\_data\_pts\_range()**

Get range of data points to read.

The range is defined from 1 to the points number (returned by [get\\_points\\_number\(\)](#)).

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_edge\_trigger\_coupling()**

Get edge trigger coupling ("ac" or "dc")

**get\_edge\_trigger\_slope()**

Get edge trigger slope ("fall" or "rise")

**get\_edge\_trigger\_source()**

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**get\_esr(*timeout=None*)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(*include=0*)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(*include=0*)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_horizontal\_offset()**

Get horizontal offset (position of the center of the sweep; in seconds)

**get\_horizontal\_span()**

Get horizontal span (in seconds)

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_points\_number**(*kind='send'*)

Get number of datapoints in various context.

*kind* defines the context. It can be "acq" (number of points acquired), "trace" (number of points in the source of the read-out trace; can be lower than "acq" if the data resolution is reduced, or if the source is not a channel data), or "send" (number of points in the sent waveform; can be lower than "trace" if [get\\_data\\_pts\\_range\(\)](#) is used to specify and incomplete range). Not all kinds are defined for all scope model (e.g., "trace" is not defined for TDS2000 series oscilloscopes).

For length of read-out trace, see also [get\\_data\\_pts\\_range\(\)](#).

**get\_probe\_attenuation**(*channel*)

Get channel probe attenuation

**get\_selected\_channel**()

Get selected source channel.

Return number if it is a real channel, or a string name otherwise.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_trigger\_level**()

Get edge trigger level (in Volts)

**get\_trigger\_mode**()

Get trigger mode.

Can be either "auto" or "norm".

**get\_trigger\_state**()

Get trigger state.

Can be "armed" (acquiring pretrigger), "ready" (pretrigger acquired, wait for trigger event), "trigger" (triggered, acquiring the rest of the waveform), "auto" ("auto" mode trigger is acquiring data in the absence of trigger), "save" (acquisition is stopped), or "scan" (oscilloscope in the scan mode)

**get\_vertical\_position**(*channel*)

Get channel vertical position (offset of the zero volt line; in V)

**get\_vertical\_span**(*channel*)

Get channel vertical span (in V)

**get\_wfmpre**(*channel=None, enable=True*)

Get preamble dictionary describing all scaling and format data for the given channel or a list of channels.

Can be acquired once and used in subsequent multiple reads to save time on re-requesting. If *channel* is None, use the currently selected channel. If *enable==True*, make sure that the requested channel is enabled; getting preamble for disabled channels raises an error.

**grab\_continuous**(*enable=True*)

Start or stop continuous grabbing

**grab\_single**(*wait=True, software\_trigger=False, wait\_timeout=None*)

Set single waveform grabbing and wait for acquisition.

If *wait==True*, wait until the acquisition is complete; otherwise, return immediately. If *software\_trigger==True*, send the software trigger after setup (i.e., the device triggers immediately regardless of the input).

**is\_channel\_enabled**(*channel*)

Check if channel is enabled

**is\_continuous**()

Check if grabbing is continuous or single

**is\_grabbing**()

Check if acquisition is in progress.

Return *True* if the oscilloscope is recording data, or if the trigger is armed/ready and waiting; return *False* if the acquisition is stopped. To check if the trigger has been triggered, use [\*get\\_trigger\\_state\(\)\*](#).

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**normalize\_channel\_name**(*channel*)

Normalize channel name as represented by the oscilloscope

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [\*DataFormat\*](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be *'raw'* (just raw data), *'string'* (with trailing and leading spaces stripped), *'int'*, *'float'*, *'bool'* (interprets *0* or *'off'* as *False*, anything else as *True*), *'value'* (returns tuple (*value*, *unit*), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of *"#"* symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**read\_multiple\_sweeps**(*channels*, *wfmpres=None*, *ensure\_fmt=False*, *timeout=None*, *return\_wfmpres=None*)

Read data from a multiple channels channel.

#### Parameters

- **channels** – list of channel indices or names
- **wfmpres** – optional list or dictionary of preambles (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout
- **return\_wfmpres** – if *True*, return tuple (*sweeps*, *wfmpres*), where *wfmpres* can be used for further sweep readouts.

**read\_raw\_data**(*channel=None*, *fmt=None*, *timeout=None*)

Request, read and parse raw data at a given channel.

*fmt* is data format (e.g., "*i1*", "<*i2*", or "*ascii*") or "*default*", which uses the default oscilloscope format (usually binary with smallest appropriate byte size). If *fmt* is *None*, use the current format. If *channel* is *None*, use the currently selected channel.

Returned data is raw (i.e., not scaled and without x axis).

**read\_sweep**(*channel*, *wfmpre=None*, *ensure\_fmt=True*, *timeout=None*)

Read data from a single channel.

#### Parameters

- **channel** – channel index or name
- **wfmpre** – optional preamble dictionary (obtained using [get\\_wfmpre\(\)](#)); if it is *None*, obtain during reading, which slows down the data acquisition a bit
- **ensure\_fmt** – if *True*, make sure that oscilloscope data format agrees with the one in *wfmpre*
- **timeout** – read timeout

**reconnect**(*new\_instrument=True*, *ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset()**

Reset the device (by default, "*\*RST*" command)

**select\_channel**(*channel*)

Select a channel to read data.

Doesn't need to be called explicitly, if [read\\_multiple\\_sweeps\(\)](#) or [read\\_sweep\(\)](#) are used.

**set\_coupling**(*channel*, *coupling='dc'*)

Set channel coupling.

Can be "*ac*", "*dc*", or "*gnd*".

**set\_data\_format**(*fmt='default'*)

Set data transfer format.

*fmt* is a string describing the format; can be either "ascii", or a numpy-style format string (e.g., "<u2"). If "default", use the oscilloscope default format (usually binary with smallest appropriate byte size).

**set\_data\_pts\_range**(*rng=None*)

Set range of data points to read.

The range is defined from 1 to the points number (returned by [get\\_points\\_number\(\)](#) with kind="acq"). If *rng* is None, set the full range.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_edge\_trigger\_coupling**(*coupling*)

Set edge trigger coupling ("ac" or "dc")

**set\_edge\_trigger\_slope**(*slope*)

Set edge trigger slope ("fall" or "rise")

**set\_edge\_trigger\_source**(*channel*)

Get edge trigger source.

Can be an integer indicating channel number or a name of a special channel.

**set\_horizontal\_offset**(*offset=0.0*)

Set horizontal offset (position of the center of the sweep; in seconds)

**set\_horizontal\_span**(*span*)

Set horizontal span (in seconds)

**set\_points\_number**(*pts\_num, reset\_limits=True*)

Set number of datapoints to record when acquiring a trace.

If *reset\_limits*==True, reset the datapoints range ([set\\_data\\_pts\\_range\(\)](#)) to the full range. The actual set value (returned by this method) can be different from the requested value.

**set\_probe\_attenuation**(*channel, attenuation*)

Set channel probe attenuation

**set\_trigger\_level**(*level*)

Set edge trigger level (in Volts)

**set\_trigger\_mode**(*trigger\_mode='auto'*)

Set trigger mode.

Can be either "auto" or "norm".

**set\_vertical\_position**(*channel, position*)

Set channel vertical position (offset of the zero volt line; in V)

**set\_vertical\_span**(*channel, span*)

Set channel vertical span (in V)

**setup\_edge\_trigger**(*source, level, coupling='dc', slope='rise'*)

Setup edge trigger.

Set source, level, coupling and slope (see corresponding methods for details).



**sleep**(*delay*)

Wait for *delay* seconds

**stop\_grabbing**()

Stop grabbing or waiting (equivalent to `self.grab_continuous(False)`)

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with `;` delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform `wait_sync()`), 'dev' (perform `wait_dev()`) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_for\_grabbing**(*timeout=None*)

Wait until the acquisition is complete

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with `" "`.
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as `'{: .3f}'`) or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string `'1;2'`); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with `" "`.
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore

later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (False by default).

- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.Thorlabs package

#### Submodules

#### pylablib.devices.Thorlabs.TLCamera module

**class** `pylablib.devices.Thorlabs.TLCamera.LibraryController`(*lib*)

Bases: `LibraryController`

**close**(*opid*)

Mark device closing.

Return tuple (`close_result`, `uninit_result`) with the results of the closing and the shutdown. If library does not need to be shut down yet, set `uninit_result=None`

**get\_opened\_num**()

Get number of opened devices

**open**()

Mark device opening.

Return tuple (`init_result`, `open_result`, `opid`) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set `init_result=None`

**preinit**()

Pre-initialize the library, if it hasn't been done already

**shutdown**()

Close all opened connections and shutdown the library

**temp\_open**()

Context for temporarily opening a new device connection

`pylablib.devices.Thorlabs.TLCamera.list_cameras`()

List connected TLCamera cameras

`pylablib.devices.Thorlabs.TLCamera.get_cameras_number`()

Get number of connected TLCamera cameras

**class** `pylablib.devices.Thorlabs.TLCamera.TDeviceInfo`(*model*, *name*, *serial\_number*,  
*firmware\_version*)

Bases: `tuple`

**firmware\_version**

**model****name****serial\_number****class** pylablib.devices.Thorlabs.TLCamera.**TSensorInfo**(*sensor\_type, bit\_depth*)Bases: [tuple](#)**bit\_depth****sensor\_type****class** pylablib.devices.Thorlabs.TLCamera.**TColorInfo**(*filter\_array\_phase, correction\_matrix, default\_white\_balance\_matrix*)Bases: [tuple](#)**correction\_matrix****default\_white\_balance\_matrix****filter\_array\_phase****class** pylablib.devices.Thorlabs.TLCamera.**TColorFormat**(*color\_format, color\_space*)Bases: [tuple](#)**color\_format****color\_space****class** pylablib.devices.Thorlabs.TLCamera.**TFrameInfo**(*frame\_index, framestamp, pixelclock, pixeltype, offset*)Bases: [tuple](#)**frame\_index****framestamp****offset****pixelclock****pixeltype****class** pylablib.devices.Thorlabs.TLCamera.**ThorlabsTLCamera**(*serial=None*)Bases: [IBinROICamera](#), [IExposureCamera](#)

Thorlabs TSI camera.

**Parameters****serial** ([str](#)) – camera serial number; can be either a string obtained using [list\\_cameras\(\)](#) function, or None, which means connecting to the first available camera (not recommended unless only one camera is connected)**Error** = <Mock name='mock.ThorlabsTLCameraError' id='140527546402640'>**TimeoutError** = <Mock spec='str' id='140527539889424'>**open()**

Open connection to the camera

**close()**

Close connection to the camera

**is\_opened()**

Check if the device is connected

**get\_device\_info()**

Get camera model data.

Return tuple (model, name, serial\_number, firmware\_version).

**get\_sensor\_info()**

Get camera sensor info.

Return tuple (sensor\_type, bit\_depth), where sensor type is "mono", "bayer", or "mono\_pol", and bit depth is an integer.

**get\_color\_info()**

Get camera color info.

Return tuple (filter\_array\_phase, correction\_matrix, default\_white\_balance\_matrix), or None if the sensor type is not "bayer".

**get\_white\_balance\_matrix()**

Get the white balance matrix

**set\_white\_balance\_matrix(matrix=None)**

Set the white balance matrix.

Can be None (the default matrix), a 3-number 1D array (multipliers for RGB), or a full 3x3 matrix.

**set\_color\_format(color\_output='auto', color\_space='linear')**

Set camera color format.

*color\_output* determines the output frame format, and can be "raw" (raw pixel values without debayering), "rgb" (color images with the color corresponding to the last array axis), "grayscale" (average of the colored images), or "auto" ("rgb" for cameras supporting color and "raw" otherwise). Note that setting "rgb" for monochrome cameras is not allowed. *color\_space* defines the output color space, and can be "linear" (linear in the pixel values), or "srgb" (sRGB color space, which is a non-linear transformation of the linear values).

**get\_color\_format()**

Get camera color format as a tuple (color\_output, color\_space)

**class RingBuffer**

Bases: `object`

Frames ring buffer.

Reacts to each new frame and stores it in the internal buffer.

**reset()**

Reset buffer and internal counters

**setup(buffsize, frame\_dim)**

Setup a new buffer with the given maximal number of frames and frame dimensions

**cleanup()**

Cleanup the buffer

**new\_frame**(*handle, buffer, idx, metadata, metadata\_size, context*)  
Callback for receiving a new frame

**wait\_for\_frame**(*idx=None, timeout=None*)  
Wait for a new frame acquisition

**get\_frame**(*idx*)  
Get the frame with the given index (or None if it is outside the buffer range)

**get\_status**()  
Get buffer status (acquired, missed, stored)

**get\_frame\_timings**()  
Get acquisition timing.  
Return tuple (exposure, frame\_period).

**set\_exposure**(*exposure*)  
Set camera exposure

**get\_frame\_period\_range**()  
Get minimal and maximal frame period (s)

**set\_frame\_period**(*frame\_period*)  
Set camera frame period.  
If it is 0 or None, set to the auto-rate mode, which automatically selects the highest frame rate.

**get\_trigger\_mode**()  
Get trigger mode.  
Can be "int" (internal/software), "ext" (external/hardware), or "bulb" (bulb trigger).

**set\_trigger\_mode**(*mode*)  
Set trigger mode.  
Can be "int" (internal/software), "ext" (external/hardware), or "bulb" (bulb trigger).

**get\_ext\_trigger\_parameters**()  
Return external trigger polarity

**setup\_ext\_trigger**(*polarity*)  
Setup external trigger polarity ("rise" or "fall")

**send\_software\_trigger**()  
Send software trigger signal

**get\_pixel\_correction\_parameters**()  
Return pixel correction parameters (enabled, threshold)

**setup\_pixel\_correction**(*enable=True, threshold=None*)  
Enable or disable hotpixel correction and set its threshold (None means keep unchanged)

**get\_gain\_range**()  
Return the available gain range (in dB)

**get\_gain**()  
Return the current gain (in dB)

**set\_gain**(*gain*, *truncate=True*)

Set the current gain (in dB).

If *truncate==True*, truncate the value to lie within the allowed range; otherwise, out-of-range values cause an error.

**get\_black\_level\_range**()

Return the available black level range

**get\_black\_level**()

Return the current black level

**set\_black\_level**(*level*, *truncate=True*)

Set the current black level.

If *truncate==True*, truncate the value to lie within the allowed range; otherwise, out-of-range values cause an error.

**is\_nir\_boost\_enabled**()

Check if NIR boost is enabled

**enable\_nir\_boost**(*enable=True*)

Enable or disable NIR boost

**is\_cooling\_enabled**()

Check if cooling is enabled

**enable\_cooling**(*enable=True*)

Enable or disable cooling

**is\_led\_enabled**()

Check if led is enabled

**enable\_led**(*enable=True*)

Enable or disable led

**get\_timestamp\_clock\_frequency**()

Return frequency of the frame timestamp clock (in Hz)

**setup\_acquisition**(*nframes=100*)

Setup acquisition.

*nframes* determines number of size of the ring buffer (by default, 100).

**clear\_acquisition**()

Clear acquisition settings

**start\_acquisition**(*frames\_per\_trigger='default'*, *auto\_start=True*, *nframes=None*)

Start camera acquisition.

#### Parameters

- **frames\_per\_trigger** – number of frames to acquire per trigger (software or hardware); *None* means unlimited number; by default, set to *None* for software trigger (i.e., run until stopped), and 1 for hardware trigger (i.e., one frame per trigger pulse)
- **auto\_start** – if *True* and the trigger is set into software mode, automatically start recording; otherwise, only start recording when [send\\_software\\_trigger\(\)](#) is called explicitly; this value is meaningless in the hardware or bulb trigger mode
- **nframes** – number of frames in the ring buffer

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend, hbin, vbin). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi(hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits(hbin=1, vbin=1)**

Get the minimal and maximal ROI parameters.

Return tuple (hlim, vlim), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (first, last) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek*==True, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==True, return tuple (frames, infos), where *infos* is a list of *TFrameInfo* instances describing frame index and frame metadata, which contains framestamp, pixel clock, pixel format, and pixel offset; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is None. if *return\_rng*==True, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

**FrameTransferError**

alias of *DefaultFrameTransferError*

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_exposure()**

Get current exposure

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period()**

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(*include=0*)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(*include=0*)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.



**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_newest\_image(peek=False, return\_info=False)**

Read the newest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (frame, info), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

**pylablib.devices.Thorlabs.base module****exception** pylablib.devices.Thorlabs.base.**ThorlabsError**Bases: *DeviceError*

Generic Thorlabs error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Thorlabs.base.**ThorlabsBackendError**(*exc*)Bases: *ThorlabsError*, *DeviceBackendError*

Thorlabs backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Thorlabs.base.**ThorlabsTimeoutError**Bases: *ThorlabsError*

Thorlabs timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args****with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**pylablib.devices.Thorlabs.elliptec module**pylablib.devices.Thorlabs.elliptec.**muxaddr**(\*args, argname='addr', \*\*kwargs)

Multiplex the function over its addr argument

**class** pylablib.devices.Thorlabs.elliptec.**TDeviceInfo**(*serial\_no*, *model\_no*, *year*, *fw\_ver*, *hw\_ver*,  
*travel*, *pulse*)Bases: *tuple***fw\_ver****hw\_ver****model\_no****pulse**

**serial\_no**

**travel**

**year**

```
class pylablib.devices.Thorlabs.elliptec.TMotorInfo(loop, motor, current, ramp_up, ramp_down,
                                                    fw_freq, bk_freq)
```

Bases: [tuple](#)

**bk\_freq**

**current**

**fw\_freq**

**loop**

**motor**

**ramp\_down**

**ramp\_up**

```
class pylablib.devices.Thorlabs.elliptec.ElliptecMotor(conn, addr='all', default_addr=None,
                                                         scale='stage', timeout=3.0,
                                                         valid_status=('ok', 'mech_timeout'))
```

Bases: [ICommBackendWrapper](#)

Basic Elliptec stage device.

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **addr** – list of device addresses (between 0 and 15) connected to this serial port; if "all", automatically detect all connected devices
- **default\_addr** – address used by default when not supplied; by default, use the first address among the connected
- **scale** – scale of the position units to the internals units; can be "stage" (use stage units such as mm or deg based on its internal calibration), "step" (directly use step units), or a number which multiplies user-supplied units to produce steps
- **timeout** – default communication timeout
- **valid\_status** – status which are considered valid and do not raise an error on status check

#### Error

alias of [ThorlabsError](#)

**get\_connected\_addrs()**

Get a list of all connected device addresses

**update\_connected\_addrs(addr=None)**

Update the list of connected device addresses

**get\_default\_addr()**

Get the current default address

**set\_default\_addr**(*addr*)

Set the current default address

**using\_default\_addr**(*addr*)

Context manager which temporarily changes the default address

**send\_comm**(*comm*, *data*="", *addr*=None)

Send a message with the given data to the devices at a given address.

For details, see ELLx communications protocol.

**class CommData**(*comm*, *data*, *addr*)

Bases: `tuple`

**addr**

**comm**

**data**

**recv\_comm**(*comm*=None, *addr*=None, *datalen*='auto', *timeout*=None)

Receive a message.

*comm*, *addr*, and *datalen* can specify the expected return command, address, or the length of the data field (if "auto", determine based on the return command). *timeout* specifies the waiting timeout (by default, same as supplied upon the device connection).

For details, see ELLx communications protocol.

**query**(*comm*, *data*="", *addr*=None, *reply\_comm*=None, *reply\_addr*='auto', *reply\_datalen*='auto', *timeout*=None)

Send a query to the device and receive the reply.

A combination of `send_comm()` and `recv_comm()`.

**add\_background\_comm**(*comm*)

Mark given *comm* as a ‘background’ message, which can be sent by the device at any point without prompt (e.g., some operation confirmation).

If it is received instead during `recv_comm` or `query` operations, it is ignored, and the corresponding counter is increased.

**check\_background\_comm**(*comm*, *addr*=None)

Return message counter and the last message value (None if not message received yet) of a given ‘background’ message received from the given address

**change\_addr**(*newaddr*, *addr*=None)

Change the device address to a new value (between 0 and 15)

**store\_parameters**(*addr*=None)

Store current device parameters (e.g., frequencies) to the energy-independent memory

**get\_device\_info**(*addr*=None)

Get device info.

Return tuple (*serial\_no*, *model\_no*, *year*, *fw\_ver*, *hw\_ver*, *travel*, *pulse*).

**get\_status**(*addr*=None)

Get device status

**get\_motor\_info**(*motor=1, addr=None*)

Get info for a given motor (between 1 and 3).

Return tuple (loop\_ena, motor\_ena, current, ramp\_up, ramp\_down, fw\_freq, bk\_freq).

**get\_scale**(*addr=None*)

Get scale parameter for the specified address.

Can be "stage", "step", or a proportionality coefficient.

**set\_scale**(*scale, addr=None*)

Set scale parameter for the specified address.

Can be "stage", "step", or a proportionality coefficient.

**home**(*home\_dir='cw', paddles='all', addr=None*)

Home the device.

The operation is synchronous, i.e., it will not finish until the homing is done. If the device is a rotary stage, then *home\_dir* specifies homing direction ("cw" or "ccw"). If the device is a paddle polarization controller, then *paddles* is a list of all paddle indices (1 to 3) to home ("all" is the same as [1, 2, 3]).

**get\_home\_offset**(*addr=None*)

Get homing offset

**set\_home\_offset**(*offset, addr=None*)

Set homing offset (note: the manufacturer advises against it)

**get\_velocity**(*addr=None*)

Get velocity as a percentage from the maximal velocity (0 to 100)

**set\_velocity**(*velocity=100, addr=None*)

Set velocity as a percentage from the maximal velocity (0 to 100)

**get\_frequency**(*motor=1, addr=None*)

Get frequencies at a given motor as a tuple (fw\_freq, bk\_freq)

**set\_frequency**(*fw\_freq=None, bk\_freq=None, motor=1, addr=None*)

Set frequencies at a given motor.

Values set as None stay the same.

**search\_frequency**(*motor=1, addr=None*)

Run the automated frequency search on a given motor.

The position might change slightly throughout the process.

**get\_position**(*addr=None*)

Get the current position

**move\_to**(*position, addr=None, timeout=30.0*)

Move to the given position.

The operation is synchronous, i.e., it will not finish until the motion is stopped. Return True if the position was reached successfully or False otherwise.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**move\_by(distance, addr=None, timeout=30.0)**

Move by the given distance.

The operation is synchronous, i.e., it will not finish until the motion is stopped. Return True if the position was reached successfully or False otherwise.

**open()**

Open the backend

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**pylablib.devices.Thorlabs.kinesis module**

`pylablib.devices.Thorlabs.kinesis.list_kinesis_devices(filter_ids=True)`

List all Thorlabs APT/Kinesis devices connected to this PC.

**Return list of tuples (conn, description).**

If `filter_ids==True`, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**class** `pylablib.devices.Thorlabs.kinesis.TDeviceInfo`(*serial\_no, model\_no, fw\_ver, hw\_type, hw\_ver, mod\_state, nchannels, notes*)

Bases: `tuple`

**fw\_ver**

**hw\_type**

**hw\_ver**

**mod\_state**

**model\_no**

**nchannels**

**notes**

**serial\_no**

**class** `pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice`(*conn, timeout=3.0, is\_rack\_system=False*)

Bases: `ICommBackendWrapper`

Generic Kinesis device.

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

**Parameters**

- **conn** – serial connection parameters (usually an 8-digit device serial number).
- **is\_rack\_system** – specify whether the device is a rack system or a standalone USB device (default mode).

**Error**

alias of `ThorlabsError`

**static** `list_devices`(*filter\_ids=True*)

List all connected devices.

Return list of tuples (conn, description). If `filter_ids==True`, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**send\_comm**(*messageID, param1=0, param2=0, source=1, dest='host'*)

Send a message with no associated data.

For details, see APT communications protocol.



**send\_comm\_data**(*messageID*, *data*, *source*=1, *dest*='host')

Send a message with associated data.

For details, see APT communications protocol.

**class CommShort**(*messageID*, *param1*, *param2*, *source*, *dest*)

Bases: `tuple`

**dest**

**messageID**

**param1**

**param2**

**source**

**class CommData**(*messageID*, *data*, *source*, *dest*)

Bases: `tuple`

**data**

**dest**

**messageID**

**source**

**recv\_comm**(*expected\_id*=None, *timeout*=None)

Receive a message.

Return either `BasicKinesisDevice.CommShort` or `BasicKinesisDevice.CommData` depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**flush\_comm**(*nmax*=1000)

Flush any commands in the queue.

if *nmax* is not None, it specifies the maximal number of commands to flush.

**query**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host', *replyID*=-1, *flush*='auto')

Send a query to the device and receive the reply.

A combination of `send_comm()` and `recv_comm()`. If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be *messageID*+1 (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**add\_background\_comm**(*messageID*)

Mark given *messageID* as a 'background' message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during `recv_comm_` operations, it is ignored, and the corresponding counter is increased.

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (None if not message received yet) of a given 'background' message

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (serial\_no, model\_no, fw\_ver, hw\_type, hw\_ver, mod\_state, nchannels, notes).

**get\_number\_of\_channels**()

Get number of channels on the device

**blink**(*channel=1, dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** pylablib.devices.Thorlabs.kinesis.**TVelocityParams**(*min\_velocity, acceleration, max\_velocity*)

Bases: `tuple`

**acceleration**

**max\_velocity**

**min\_velocity**

**class** pylablib.devices.Thorlabs.kinesis.**TJogParams**(*mode, step\_size, min\_velocity, acceleration, max\_velocity, stop\_mode*)

Bases: `tuple`

**acceleration**

**max\_velocity**

**min\_velocity**

**mode**

**step\_size**

**stop\_mode**

**class** pylablib.devices.Thorlabs.kinesis.**TGenMoveParams**(*backlash\_distance*)

Bases: `tuple`

**backlash\_distance**

**class** pylablib.devices.Thorlabs.kinesis.**THomeParams**(*home\_direction, limit\_switch, velocity, offset\_distance*)

Bases: `tuple`

**home\_direction**

**limit\_switch**

**offset\_distance**

**velocity**

**class** pylablib.devices.Thorlabs.kinesis.**TPolCtlParams**(*velocity, home\_position, jog1, jog2, jog3*)

Bases: `tuple`

**home\_position**

**jog1**

**jog2**

**jog3**

velocity

```
class pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams(hw_kind_cw, hw_kind_ccw,  
                                                           hw_swapped, sw_position_cw,  
                                                           sw_position_ccw, sw_kind)
```

Bases: `tuple`

hw\_kind\_ccw

hw\_kind\_cw

hw\_swapped

sw\_kind

sw\_position\_ccw

sw\_position\_cw

```
class pylablib.devices.Thorlabs.kinesis.TKCubeTrigIOParams(trig1_mode, trig1_pol, trig2_mode,  
                                                           trig2_pol)
```

Bases: `tuple`

trig1\_mode

trig1\_pol

trig2\_mode

trig2\_pol

```
class pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams(start_fw, step_fw, num_fw, start_bk,  
                                                           step_bk, num_bk, width, ncycles)
```

Bases: `tuple`

ncycles

num\_bk

num\_fw

start\_bk

start\_fw

step\_bk

step\_fw

width

```
class pylablib.devices.Thorlabs.kinesis.TPZMotorDriveParams(max_voltage, velocity, acceleration)
```

Bases: `tuple`

acceleration

max\_voltage

velocity

```
class pylablib.devices.Thorlabs.kinesis.TPZMotorJogParams(mode, step_size_fw, step_size_bk,
                                                         velocity, acceleration)
```

Bases: [tuple](#)

**acceleration**

**mode**

**step\_size\_bk**

**step\_size\_fw**

**velocity**

```
pylablib.devices.Thorlabs.kinesis.muxchannel(*args, **kwargs)
```

```
class pylablib.devices.Thorlabs.kinesis.KinesisDevice(conn, timeout=3.0, default_channel=1,
                                                       is_rack_system=False)
```

Bases: [IMultiaxisStage](#), [BasicKinesisDevice](#)

Overarching Kinesis class containing all of the necessary private methods.

Subclasses are expected to make some of them visible by renaming, and to define device variables and opening behavior accordingly.

#### Parameters

- **conn** – serial connection parameters (usually an 8-digit device serial number).
- **timeout** – device communication timeout.
- **default\_channel** – starting default channel used when no channel is supplied to a channel-level command (such as `move_to` or `get_position`).
- **is\_rack\_system** – specify whether the device is a rack system or a standalone USB device (default mode).

```
get_all_channels()
```

Get the list of all available channels; alias of `get_all_axes` method

```
set_default_channel(channel)
```

Set the default channel for all channel-related methods

```
using_channel(channel)
```

Context manager for temporarily using a different default channel

```
status_bits = [(1, 'hw_bk_lim'), (2, 'hw_fw_lim'), (4, 'sw_bk_lim'), (8,
'sw_fw_lim'), (16, 'moving_bk'), (32, 'moving_fw'), (64, 'jogging_bk'), (128,
'jogging_fw'), (256, 'connected'), (512, 'homing'), (1024, 'homed'), (2048,
'initializing'), (4096, 'tracking'), (8192, 'settled'), (16384, 'motion_error'),
(32768, 'instr_error'), (65536, 'interlock'), (131072, 'overtemp'), (262144,
'volt_supply_fault'), (524288, 'commutation_error'), (1048576, 'digio1'), (2097152,
'digio2'), (4194304, 'digio3'), (8388608, 'digio4'), (16777216, 'current_limit'),
(33554432, 'encoder_fault'), (67108864, 'overcurrent'), (134217728,
'curr_supply_fault'), (268435456, 'power_ok'), (536870912, 'active'), (1073741824,
'error'), (2147483648, 'enabled')]
```

#### Error

alias of [ThorlabsError](#)

**add\_background\_comm**(*messageID*)

Mark given *messageID* as a ‘background’ message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during `recv_comm_` operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1*, *dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (None if not message received yet) of a given ‘background’ message

**close**()

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not None, it specifies the maximal number of commands to flush.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (*serial\_no*, *model\_no*, *fw\_ver*, *hw\_type*, *hw\_ver*, *mod\_state*, *nchannels*, *notes*).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_number\_of\_channels**()

Get number of channels on the device

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

### **is\_opened()**

Check if the device is connected

### **static list\_devices(filter\_ids=True)**

List all connected devices.

Return list of tuples (`conn`, `description`). If `filter_ids==True`, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

### **lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

### **locking(timeout=None)**

Context manager for lock & unlock

### **open()**

Open the backend

### **query(messageID, param1=0, param2=0, source=1, dest='host', replyID=-1, flush='auto')**

Send a query to the device and receive the reply.

A combination of `send_comm()` and `recv_comm()`. If `replyID` is not `None`, specifies the expected reply message ID; if -1 (default), set to be `messageID+1` (the standard convention). `flush` specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

### **recv\_comm(expected\_id=None, timeout=None)**

Receive a message.

Return either `BasicKinesisDevice.CommShort` or `BasicKinesisDevice.CommData` depending on the message type (fixed length with two parameters, or variable length with associated data). If `expected_id` is not `None` and the received message ID is different from `expected_id`, raise an error. If `timeout` is not `None`, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

### **remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

`mapping` is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by `get_all_axes()`), or a dictionary `{alias: original}` of the new axes aliases.

### **send\_comm(messageID, param1=0, param2=0, source=1, dest='host')**

Send a message with no associated data.

For details, see APT communications protocol.

### **send\_comm\_data(messageID, data, source=1, dest='host')**

Send a message with associated data.

For details, see APT communications protocol.

### **set\_device\_variable(key, value)**

Set the value of a settings parameter

### **unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

```
class pylablib.devices.Thorlabs.kinesis.TFlipperParameters(transit_time, io1_oper_mode,  
                                                         io1_sig_mode, io1_pulse_width,  
                                                         io2_oper_mode, io2_sig_mode,  
                                                         io2_pulse_width)
```

Bases: `tuple`

`io1_oper_mode`

`io1_pulse_width`

`io1_sig_mode`

`io2_oper_mode`

`io2_pulse_width`

`io2_sig_mode`

`transit_time`

```
class pylablib.devices.Thorlabs.kinesis.MFF(conn)
```

Bases: `KinesisDevice`

MFF (Motorized Filter Flip Mount) device.

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

#### Parameters

**conn** – serial connection parameters (usually 8-digit device serial number).

```
get_status_n(channel=None)
```

Get numerical status of the device.

For details, see APT communications protocol.

```
get_status(channel=None)
```

Get device status.

Return list of status strings, which can include "hw\_fw\_lim" (forward hardware limit switch reached), "hw\_bk\_lim" (backward hardware limit switch reached), "sw\_fw\_lim" (forward software limit switch reached), "sw\_bk\_lim" (backward software limit switch reached), "moving\_fw" (moving forward), "moving\_bk" (moving backward), "jogging\_fw" (jogging forward), "jogging\_bk" (jogging backward), "connected" (motor is connected), "homing" (homing), "homed" (homing done), "initializing" (3-phase motor phase initialization), "tracking" (position is within trajectory), "settled" (position has been stable), "motion\_error" (excessive position error), "instr\_error" (legacy instrument command error), "interlock" (interlock is on), "overtemp" (temperature above limit), "volt\_supply\_fault" (supply voltage is too low), "commutation\_error" (3-phase motor commutation error), "digio1" (state of digital input 1), "digio2" (state of digital input 2), "digio3" (state of digital input 3), "digio4" (state of digital input 4), "current\_limit" (motor current limit exceeded for a long time), "encoder\_fault" (encoder problems), "overcurrent" (motor current limit exceeded temporarily), "curr\_supply\_fault" (current drawn from supply is too high), "power\_ok" (power is ok), "active" (moving), "error" (any error), "enabled" (motor is enabled).

```
wait_for_status(status, enabled, channel=None, timeout=None, period=0.05)
```

Wait until the given status (or list of status bits) is in the desired state.

*status* is a string or a list of strings describing the status bits to monitor; for possible values, see `get_status()`. If *enabled*==True, wait until one of the given statuses is enabled; otherwise, wait until all given statuses are disabled. *period* specifies status checking period (in s).



**move\_to\_state**(*state*, *channel=None*)

Move to the given flip mount state (either 0 or 1)

**get\_state**(*channel=None*)

Get the flip mount state (either 0 or 1).

Return None if the mount is current moving (i.e., the state os undefined)

**get\_flipper\_parameters**(*channel=None*)

Get current flipper parameters (*transit\_time*, *io1\_oper\_mode*, *io1\_sig\_mode*, *io1\_pulse\_width*, *io2\_oper\_mode*, *io2\_sig\_mode*, *io2\_pulse\_width*)

*transit\_time* specifies transit time (in seconds between 0.3 and 2.8); *io\*\_oper\_mode* specifies operation mode (in vs. out and position vs. motion input/indication), *io\*\_sig\_mode* specifies signal mode (button input, voltage edge input, edge output or pulse output). *io\*\_pulse\_width* specifies output pulse width if the corresponding output mode is selected. For detailed mode description, see the flip mirror or APT manual.

**setup\_flipper**(*transit\_time=None*, *io1\_oper\_mode=None*, *io1\_sig\_mode=None*, *io1\_pulse\_width=None*, *io2\_oper\_mode=None*, *io2\_sig\_mode=None*, *io2\_pulse\_width=None*, *channel=None*)

Set flipper parameters.

*transit\_time* specifies transit time (in seconds between 0.3 and 2.8); *io\*\_oper\_mode* specifies operation mode (in vs. out and position vs. motion input/indication), *io\*\_sig\_mode* specifies signal mode (button input, voltage edge input, edge output or pulse output). *io\*\_pulse\_width* specifies output pulse width if the corresponding output mode is selected. If any parameter is None, use the current value. For detailed mode description, see the flip mirror or APT manual.

## Error

alias of [\*ThorlabsError\*](#)

**add\_background\_comm**(*messageID*)

Mark given *messageID* as a ‘background’ message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during *recv\_comm* operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1*, *dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (None if not message received yet) of a given ‘background’ message

**close**()

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not None, it specifies the maximal number of commands to flush.

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_all\_channels()**

Get the list of all available channels; alias of `get_all_axes` method

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (serial\_no, model\_no, fw\_ver, hw\_type, hw\_ver, mod\_state, nchannels, notes).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_number\_of\_channels()**

Get number of channels on the device

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**static list\_devices**(*filter\_ids=True*)

List all connected devices.

Return list of tuples (conn, description). If *filter\_ids==True*, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend

**query**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host', *replyID*=-1, *flush*='auto')

Send a query to the device and receive the reply.

A combination of [send\\_comm\(\)](#) and [recv\\_comm\(\)](#). If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be *messageID*+1 (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**recv\_comm**(*expected\_id*=None, *timeout*=None)

Receive a message.

Return either [BasicKinesisDevice.CommShort](#) or [BasicKinesisDevice.CommData](#) depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**remap\_axes**(*mapping*, *accept\_original*=True)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**send\_comm**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host')

Send a message with no associated data.

For details, see APT communications protocol.

**send\_comm\_data**(*messageID*, *data*, *source*=1, *dest*='host')

Send a message with associated data.

For details, see APT communications protocol.

**set\_default\_channel**(*channel*)

Set the default channel for all channel-related methods

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

```
status_bits = [(1, 'hw_bk_lim'), (2, 'hw_fw_lim'), (4, 'sw_bk_lim'), (8,
'hw_fw_lim'), (16, 'moving_bk'), (32, 'moving_fw'), (64, 'jogging_bk'), (128,
'jogging_fw'), (256, 'connected'), (512, 'homing'), (1024, 'homed'), (2048,
'initializing'), (4096, 'tracking'), (8192, 'settled'), (16384, 'motion_error'),
(32768, 'instr_error'), (65536, 'interlock'), (131072, 'overtemp'), (262144,
'volt_supply_fault'), (524288, 'commutation_error'), (1048576, 'digio1'), (2097152,
'digio2'), (4194304, 'digio3'), (8388608, 'digio4'), (16777216, 'current_limit'),
(33554432, 'encoder_fault'), (67108864, 'overcurrent'), (134217728,
'curr_supply_fault'), (268435456, 'power_ok'), (536870912, 'active'), (1073741824,
'error'), (2147483648, 'enabled')]
```

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_channel**(*channel*)

Context manager for temporarily using a different default channel

```
class pylablib.devices.Thorlabs.kinesis.KinesisMotor(conn, scale='step', default_channel=1,
                                                    is_rack_system=False)
```

Bases: [KinesisDevice](#)

Thorlabs motor controller.

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

The physical units are encoder steps for position (ratio to m or degrees depends on the connected stage), steps/sec for velocity, and steps/sec<sup>2</sup> for acceleration.

#### Parameters

- **conn** (*str*) – serial connection parameters (usually an 8-digit device serial number).
- **scale** – scale of the position, velocity, and acceleration units to the internal units; can be "stage" (attempt to autodetect motor and stage parameters), a string with the name of the stage, e.g., "MTS50-Z8" or "DDR100" (use the stage name to extract the scale; determine velocity and acceleration from this scale and the motor model), "step" (use encoder/motor steps as units; determine velocity and acceleration from this scale and the motor model), a single number (use this as the ratio of internal steps to physical units; determine velocity and acceleration from this scale and the motor model), or a 3-tuple of numbers (**position\_scale**, **velocity\_scale**, **acceleration\_scale**) which gives the ratio of internal units to physical units (useful for new or unrecognized controllers or stages, as no autodetection is required); in the case of unrecognized devices, use internal units (same as setting **scale**=(1,1,1)); if the scale can't be autodetected, it can be obtained from the APT manual knowing the device and the stage model
- **default\_channel** – starting default channel used when no channel is supplied to a channel-level command (such as **move\_to** or **get\_position**).
- **is\_rack\_system** – specify whether the device is a rack system or a standalone USB device (default mode).

#### **get\_scale()**

Get the scaling coefficients.

Return a tuple (**position\_scale**, **velocity\_scale**, **acceleration\_scale**) for scaling of the physical units in terms of internal units. To get the coefficients source and physical units, use [get\\_scale\\_units\(\)](#).

#### **get\_scale\_units()**

Get units used for calculating scaled position, velocity and acceleration values.

Can be "deg" (autodetected rotational stage: deg, deg/s and deg/s<sup>2</sup>), "m" (autodetected translational stage: m, m/sec and m/sec<sup>2</sup>), "step" (autodetected driver but not detected step scale: steps, steps/sec and steps/sec<sup>2</sup>) "user\_step" (autodetected driver and user supplied step scale: user-supplied step scale for position, same units per sec or sec<sup>2</sup> for velocity and acceleration), "user" (all three scales are supplied by user), or "internal" (no scales are supplied or detected, use device internal units)

#### **get\_stage()**

Return the name of the stage which was supplied by the user or autodetected.

If the stage is unknown, return None

#### **set\_supported\_channels(channels=1)**

Set the channels in the device.

Can be either a list of channels, a single number defining the number of channels numbered from 1 to **channels** (inclusive).

**get\_status\_n**(*channel=None*)

Get numerical status of the device.

For details, see APT communications protocol.

**get\_status**(*channel=None*)

Get device status.

Return list of status strings, which can include "hw\_fw\_lim" (forward hardware limit switch reached), "hw\_bk\_lim" (backward hardware limit switch reached), "sw\_fw\_lim" (forward software limit switch reached), "sw\_bk\_lim" (backward software limit switch reached), "moving\_fw" (moving forward), "moving\_bk" (moving backward), "jogging\_fw" (jogging forward), "jogging\_bk" (jogging backward), "connected" (motor is connected), "homing" (homing), "homed" (homing done), "initializing" (3-phase motor phase initialization), "tracking" (position is within trajectory), "settled" (position has been stable), "motion\_error" (excessive position error), "instr\_error" (legacy instrument command error), "interlock" (interlock is on), "overtemp" (temperature above limit), "volt\_supply\_fault" (supply voltage is too low), "commutation\_error" (3-phase motor commutation error), "digio1" (state of digital input 1), "digio2" (state of digital input 2), "digio3" (state of digital input 3), "digio4" (state of digital input 4), "current\_limit" (motor current limit exceeded for a long time), "encoder\_fault" (encoder problems), "overcurrent" (motor current limit exceeded temporarily), "curr\_supply\_fault" (current drawn from supply is too high), "power\_ok" (power is ok), "active" (moving), "error" (any error), "enabled" (motor is enabled).

**wait\_for\_status**(*status, enabled, channel=None, timeout=None, period=0.05*)

Wait until the given status (or list of status bits) is in the desired state.

*status* is a string or a list of strings describing the status bits to monitor; for possible values, see [get\\_status\(\)](#). If *enabled==True*, wait until one of the given statuses is enabled; otherwise, wait until all given statuses are disabled. *period* specifies status checking period (in s).

**home**(*sync=True, force=False, channel=None, timeout=None*)

Home the device.

If *sync==True*, wait until homing is done (with the given timeout). If *force==False*, only home if the device isn't homed already.

**is\_homing**(*channel=None*)

Check if homing is in progress

**is\_homed**(*channel=None*)

Check if the device is homed

**wait\_for\_home**(*channel=None, timeout=None*)

Wait until the device is homed

**get\_position**(*channel=None, scale=True*)

Get current position.

If *scale==True*, return value in the physical units (see class description); otherwise, return it in the device internal units (steps).

**set\_position\_reference**(*position=0, channel=None, scale=True*)

Set position reference (actual motor position stays the same).

If *scale==True*, assume that the position is in the physical units (see class description); otherwise, assume it is in the device internal units (steps).

**move\_by**(*distance=1, channel=None, scale=True*)

Move by a given amount (positive or negative) from the current position.

If *scale==True*, assume that the distance is in the physical units (see class description); otherwise, assume it is in the device internal units (steps).

**move\_to**(*position, channel=None, scale=True*)

Move to *position* (positive or negative).

If *scale==True*, assume that the position is in the physical units (see class description); otherwise, assume it is in the device internal units (steps).

**jog**(*direction, channel=None, kind='continuous'*)

Jog in the given direction ("+" or "-").

If *kind=="continuous"*, simply start motion in the given direction at the maximal speed until either the motor is stopped explicitly, or the limit is reached (this uses MOT\_MOVE\_VELOCITY command). If *kind=="builtin"*, use the built-in MOT\_MOVE\_JOG command, whose parameters are specified by [`get\_jog\_parameters\(\)`](#).

**is\_moving**(*channel=None*)

Check if motion is in progress

**wait\_move**(*channel=None, timeout=None*)

Wait until motion command is done

**stop**(*immediate=False, sync=True, channel=None, timeout=None*)

Stop the motion.

If *immediate==True* make an abrupt stop; otherwise, slow down gradually. If *sync==True*, wait until the motion is stopped.

**wait\_for\_stop**(*channel=None, timeout=None*)

Wait until motion or homing is done

**get\_velocity\_parameters**(*channel=None, scale=True*)

Get current velocity parameters (*min\_velocity*, *acceleration*, *max\_velocity*)

Note that, according to the documentation, the minimal velocity is always zero. If *scale==True*, return values in the physical units (see class description); otherwise, return it in the device internal units.

**setup\_velocity**(*min\_velocity=None, acceleration=None, max\_velocity=None, channel=None, scale=True*)

Set velocity parameters.

If any parameter is *None*, use the current value. Note that, according to the documentation, the minimal velocity is always zero, so changing it has no effect. If *scale==True*, assume that the specified values are in the physical units (see class description); otherwise, assume it is in the device internal units.

**get\_jog\_parameters**(*channel=None, scale=True*)

Get current jog parameters (*mode*, *step\_size*, *min\_velocity*, *acceleration*, *max\_velocity*, *stop\_mode*)

If *scale==True*, return values in the physical units (see class description); otherwise, return it in the device internal units.

**setup\_jog**(*mode=None, step\_size=None, min\_velocity=None, acceleration=None, max\_velocity=None, stop\_mode=None, channel=None, scale=True*)

Set jog parameters.

If any parameter is *None*, use the current value. If *scale==True*, assume that the specified values are in the physical units (see class description); otherwise, assume it is in the device internal units.

**get\_homing\_parameters**(*channel=None, scale=True*)

Get current homing parameters (*home\_direction, limit\_switch, velocity, offset\_distance*)

If *scale==True*, return values are in the physical units (see class description); otherwise, return it in the device internal units.

**setup\_homing**(*home\_direction=None, limit\_switch=None, velocity=None, offset\_distance=None, channel=None, scale=True*)

Set homing parameters.

If any parameter is *None*, use the current value. If *scale==True*, assume that the specified values are in the physical units (see class description); otherwise, assume it is in the device internal units.

**get\_gen\_move\_parameters**(*channel=None, scale=True*)

Get general move parameters (*backlash\_distance*)

If *scale==True*, return values in the physical units (see class description); otherwise, return it in the device internal units.

**setup\_gen\_move**(*backlash\_distance=None, channel=None, scale=True*)

Set jog parameters.

If any parameter is *None*, use the current value. If *scale==True*, assume that the specified value is in the physical units (see class description); otherwise, assume it is in the device internal units.

**get\_limit\_switch\_parameters**(*channel=None, scale=True*)

Get current limit switch parameters (*hw\_kind\_cw, hw\_kind\_ccw, hw\_flipped, sw\_position\_cw, sw\_position\_ccw, sw\_kind*)

If *scale==True*, return values in the physical units (see class description); otherwise, return it in the device internal units (steps).

**setup\_limit\_switch**(*hw\_kind\_cw=None, hw\_kind\_ccw=None, hw\_swapped=None, sw\_position\_cw=None, sw\_position\_ccw=None, sw\_kind=None, channel=None, scale=True*)

Set limit switch parameters.

If any parameter is *None*, use the current value. If *scale==True*, assume that the specified values are in the physical units (see class description); otherwise, assume it is in the device internal units (Steps).

**get\_kcube\_trigio\_parameters**()

Get KCube trigger IO parameters (*trig1\_mode, trig1\_pol, trig2\_mode, trig2\_pol*)

**setup\_kcube\_trigio**(*trig1\_mode=None, trig1\_pol=None, trig2\_mode=None, trig2\_pol=None*)

Set KCube trigger IO parameters.

If any parameter is *None*, use the current value.

**get\_kcube\_trigpos\_parameters**(*scale=True*)

Get KCube trigger position parameters (*start\_fw, step\_fw, num\_fw, start\_bk, step\_bk, num\_bk, width, ncycles*).

If *scale==True*, return positions and steps in the physical units (see class description); otherwise, return it in the device internal units (steps). Pulse width is always defined in seconds.

**setup\_kcube\_trigpos**(*start\_fw=None, step\_fw=None, num\_fw=None, start\_bk=None, step\_bk=None, num\_bk=None, width=None, ncycles=None, scale=True*)

Set KCube trigger IO parameters.

If any parameter is `None`, use the current value.

If `scale==True`, return positions and steps in the physical units (see class description); otherwise, return it in the device internal units (steps). Pulse width is always defined in seconds.

**get\_polctl\_parameters**(*scale=True*)

Get current polarizer controller parameters (`velocity`, `home_position`, `jog1`, `jog2`, `jog3`)

If `scale==True`, return values in the physical units (see class description); otherwise, return it in the device internal units. `velocity` is always returned in percent units (0 to 100).

**setup\_polctl**(*velocity=None, home\_position=None, jog1=None, jog2=None, jog3=None, scale=True*)

Set polarizer controller parameters.

If any parameter is `None`, use the current value. If `scale==True`, assume that the specified values are in the physical units (see class description); otherwise, assume it is in the device internal units. `velocity` is always set in percent units (0 to 100).

### Error

alias of [\*ThorlabsError\*](#)

**add\_background\_comm**(*messageID*)

Mark given `messageID` as a ‘background’ message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during `recv_comm_` operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1, dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (`None` if not message received yet) of a given ‘background’ message

**close**()

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not `None`, it specifies the maximal number of commands to flush.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_all\_channels**()

Get the list of all available channels; alias of `get_all_axes` method

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (`serial_no`, `model_no`, `fw_ver`, `hw_type`, `hw_ver`, `mod_state`, `nchannels`, `notes`).



**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_number\_of\_channels()**

Get number of channels on the device

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**static list\_devices(filter\_ids=True)**

List all connected devices.

Return list of tuples (conn, description). If *filter\_ids==True*, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**query(messageID, param1=0, param2=0, source=1, dest='host', replyID=-1, flush='auto')**

Send a query to the device and receive the reply.

A combination of [send\\_comm\(\)](#) and [recv\\_comm\(\)](#). If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be messageID+1 (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**recv\_comm(expected\_id=None, timeout=None)**

Receive a message.

Return either [BasicKinesisDevice.CommShort](#) or [BasicKinesisDevice.CommData](#) depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not

None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**send\_comm**(*messageID*, *param1=0*, *param2=0*, *source=1*, *dest='host'*)

Send a message with no associated data.

For details, see APT communications protocol.

**send\_comm\_data**(*messageID*, *data*, *source=1*, *dest='host'*)

Send a message with associated data.

For details, see APT communications protocol.

**set\_default\_channel**(*channel*)

Set the default channel for all channel-related methods

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

```
status_bits = [(1, 'hw_bk_lim'), (2, 'hw_fw_lim'), (4, 'sw_bk_lim'), (8,
'sw_fw_lim'), (16, 'moving_bk'), (32, 'moving_fw'), (64, 'jogging_bk'), (128,
'jogging_fw'), (256, 'connected'), (512, 'homing'), (1024, 'homed'), (2048,
'initializing'), (4096, 'tracking'), (8192, 'settled'), (16384, 'motion_error'),
(32768, 'instr_error'), (65536, 'interlock'), (131072, 'overtemp'), (262144,
'volt_supply_fault'), (524288, 'commutation_error'), (1048576, 'digio1'), (2097152,
'digio2'), (4194304, 'digio3'), (8388608, 'digio4'), (16777216, 'current_limit'),
(33554432, 'encoder_fault'), (67108864, 'overcurrent'), (134217728,
'curr_supply_fault'), (268435456, 'power_ok'), (536870912, 'active'), (1073741824,
'error'), (2147483648, 'enabled')]
```

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_channel**(*channel*)

Context manager for temporarily using a different default channel

**class** `pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor`(*conn*, *default\_channel=1*)

Bases: [KinesisDevice](#)

Thorlabs piezo motor (TIM/KIM series) controller.

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

#### Parameters

**conn** (*str*) – serial connection parameters (usually an 8-digit device serial number).

**get\_enabled\_channels**()

Check which specific piezo motor channels are enabled.

Can be None (none enabled), or a tuple with either one or two channels: (1,) to (4,), (1,2) or (3,4).

**enable\_channels**(*channel*)

Enable specific piezo motor channel.

Can be None (none enabled), and integer 1 to 4, or a tuple (1, 2) or (3, 4) (enable 2 channel simultaneously).

**get\_status\_n**(*channel=None*)

Get numerical status of the piezo motor.

For details, see APT communications protocol.

**get\_status**(*channel=None*)

Get piezo motor status.

Return list of status strings, which can include "sw\_fw\_lim" (forward limit switch reached), "sw\_bk\_lim" (backward limit switch reached), "moving\_fw" (moving forward), "moving\_bk" (moving backward), "jogging\_fw" (jogging forward), "jogging\_bk" (jogging backward), "homing" (homing), "homed" (homing done), "tracking", "settled", "motion\_error" (excessive position error), "current\_limit" (motor current limit exceeded), or "enabled" (motor is enabled).

**wait\_for\_status**(*status, enabled, timeout=None, period=0.05, channel=None*)**get\_position**(*channel=None*)

Get current piezo-motor position

**set\_position\_reference**(*position=0, channel=None*)

Set piezo-motor position reference (actual position stays the same)

**move\_by**(*distance=1, auto\_enable=True, channel=None*)

Move piezo-motor by a given *distance* (positive or negative)

**move\_to**(*position, auto\_enable=True, channel=None*)

Move piezo-motor to *position* (positive or negative)

**jog**(*direction, kind='continuous', auto\_enable=True, channel=None*)

Jog piezo motor in the given direction ("+" or "-").

If *kind*=="continuous", simply start motion in the given direction at the standard jog speed until either the motor is stopped explicitly, or the limit is reached. If *kind*=="builtin", use the built-in jog command, whose parameters are specified by [get\\_jog\\_parameters\(\)](#). Note that *kind*=="continuous" is still implemented through the builtin jog, so it changes its parameters; hence, afterwards the jog parameters need to be manually restored.

**is\_moving**(*channel=None*)

Check if motion is in progress

**wait\_move**(*channel=None, timeout=None*)

Wait until motion command is done

**stop**(*channel=None, sync=True*)

Stop the piezo motor motion

**get\_drive\_parameters**(*channel=None*)

Get current piezo-motor drive parameters (max\_voltage, velocity, acceleration)

Voltage is defined in volts, velocity in steps/s, and acceleration in steps/s^2.

**setup\_drive**(*max\_voltage=None, velocity=None, acceleration=None, channel=None*)

Set piezo-motor drive parameters.

If any parameter is *None*, use the current value. Voltage is defined in volts, velocity in steps/s, and acceleration in steps/s<sup>2</sup>.

**get\_jog\_parameters**(*channel=None*)

Get current piezo-motor jog parameters (*mode, step\_size\_fw, step\_size\_bk, velocity, acceleration*)

Step size is defined in piezo steps, velocity in steps/s, and acceleration in step/s<sup>2</sup>.

**setup\_jog**(*mode=None, step\_size\_fw=None, step\_size\_bk=None, velocity=None, acceleration=None, channel=None*)

Set piezo-motor jog parameters.

If any parameter is *None*, use the current value. Step size is defined in piezo steps, velocity in steps/s, and acceleration in step/s<sup>2</sup>. TIM-series controllers do not support separate step size, so *step\_size\_bk* is ignored for them.

### Error

alias of [\*ThorlabsError\*](#)

**add\_background\_comm**(*messageID*)

Mark given messageID as a ‘background’ message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during *recv\_comm* operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1, dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (*None* if not message received yet) of a given ‘background’ message

**close**()

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not *None*, it specifies the maximal number of commands to flush.

**get\_all\_axes**()

Get the list of all available axes (taking mapping into account)

**get\_all\_channels**()

Get the list of all available channels; alias of *get\_all\_axes* method

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (*serial\_no, model\_no, fw\_ver, hw\_type, hw\_ver, mod\_state, nchannels, notes*).

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_number\_of\_channels()**

Get number of channels on the device

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**static list\_devices(filter\_ids=True)**

List all connected devices.

Return list of tuples (conn, description). If *filter\_ids==True*, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**query(messageID, param1=0, param2=0, source=1, dest='host', replyID=-1, flush='auto')**

Send a query to the device and receive the reply.

A combination of [send\\_comm\(\)](#) and [recv\\_comm\(\)](#). If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be *messageID+1* (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**recv\_comm(expected\_id=None, timeout=None)**

Receive a message.

Return either [BasicKinesisDevice.CommShort](#) or [BasicKinesisDevice.CommData](#) depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not

None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**send\_comm**(*messageID*, *param1=0*, *param2=0*, *source=1*, *dest='host'*)

Send a message with no associated data.

For details, see APT communications protocol.

**send\_comm\_data**(*messageID*, *data*, *source=1*, *dest='host'*)

Send a message with associated data.

For details, see APT communications protocol.

**set\_default\_channel**(*channel*)

Set the default channel for all channel-related methods

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

```
status_bits = [(1, 'hw_bk_lim'), (2, 'hw_fw_lim'), (4, 'sw_bk_lim'), (8,
'hw_fw_lim'), (16, 'moving_bk'), (32, 'moving_fw'), (64, 'jogging_bk'), (128,
'jogging_fw'), (256, 'connected'), (512, 'homing'), (1024, 'homed'), (2048,
'initializing'), (4096, 'tracking'), (8192, 'settled'), (16384, 'motion_error'),
(32768, 'instr_error'), (65536, 'interlock'), (131072, 'overtemp'), (262144,
'volt_supply_fault'), (524288, 'commutation_error'), (1048576, 'digio1'), (2097152,
'digio2'), (4194304, 'digio3'), (8388608, 'digio4'), (16777216, 'current_limit'),
(33554432, 'encoder_fault'), (67108864, 'overcurrent'), (134217728,
'curr_supply_fault'), (268435456, 'power_ok'), (536870912, 'active'), (1073741824,
'error'), (2147483648, 'enabled')]
```

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_channel**(*channel*)

Context manager for temporarily using a different default channel

**class** `pylablib.devices.Thorlabs.kinesis.KinesisPiezoController`(*conn*)

Bases: [KinesisDevice](#)

Thorlabs piezo controller (TPZ/KPZ series).

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

#### Parameters

**conn** (*str*) – serial connection parameters (usually an 8-digit device serial number).

**is\_channel\_enabled**(*channel=None*)

Check if the given channel is enabled

**enable\_channel**(*enabled=True*, *channel=None*)

Enable or disable the given channel

**get\_status\_n**(*channel=None*)

Get numerical status of the piezo controller.

For details, see APT communications protocol.

**get\_status**(*channel=None*)

Get piezo motor status.

Return list of status strings, which can include "stage\_connected" (actuator is connected), "zeroed" (position readout actuator is zeroed), "zeroing" (position readout actuator is zeroing), "gauge\_connected" (strain gauge is connected), "closed\_loop" (operating in the closed loop mode) "active" (unit is active), "enabled" (output is enabled).

**get\_output\_voltage**(*units='V', channel=None*)

Get piezo controller output voltage

**set\_output\_voltage**(*voltage, units='V', channel=None*)

Set piezo controller output voltage

**get\_voltage\_range**(*channel=None*)

Get piezo controller output voltage range (in V)

**set\_voltage\_range**(*rng, channel=None*)

Set piezo controller output voltage range (in V)

**get\_voltage\_source**(*channel=None*)

Get piezo controller input voltage source

**set\_voltage\_source**(*src='software', channel=None*)

Set piezo controller input voltage source

## Error

alias of [\*ThorlabsError\*](#)

**add\_background\_comm**(*messageID*)

Mark given messageID as a 'background' message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during `recv_comm` operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1, dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (None if not message received yet) of a given 'background' message

**close**()

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not None, it specifies the maximal number of commands to flush.

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_all\_channels()**

Get the list of all available channels; alias of `get_all_axes` method

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (`serial_no`, `model_no`, `fw_ver`, `hw_type`, `hw_ver`, `mod_state`, `nchannels`, `notes`).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_number\_of\_channels()**

Get number of channels on the device

**get\_settings**(*include=0*)

Get dict {`name`: `value`} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**is\_opened()**

Check if the device is connected

**static list\_devices**(*filter\_ids=True*)

List all connected devices.

Return list of tuples (`conn`, `description`). If `filter_ids==True`, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open()**

Open the backend



**query**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host', *replyID*=-1, *flush*='auto')

Send a query to the device and receive the reply.

A combination of [send\\_comm\(\)](#) and [recv\\_comm\(\)](#). If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be *messageID*+1 (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**recv\_comm**(*expected\_id*=None, *timeout*=None)

Receive a message.

Return either [BasicKinesisDevice.CommShort](#) or [BasicKinesisDevice.CommData](#) depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**remap\_axes**(*mapping*, *accept\_original*=True)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {alias: original} of the new axes aliases.

**send\_comm**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host')

Send a message with no associated data.

For details, see APT communications protocol.

**send\_comm\_data**(*messageID*, *data*, *source*=1, *dest*='host')

Send a message with associated data.

For details, see APT communications protocol.

**set\_default\_channel**(*channel*)

Set the default channel for all channel-related methods

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

```
status_bits = [(1, 'hw_bk_lim'), (2, 'hw_fw_lim'), (4, 'sw_bk_lim'), (8,
'hw_fw_lim'), (16, 'moving_bk'), (32, 'moving_fw'), (64, 'jogging_bk'), (128,
'jogging_fw'), (256, 'connected'), (512, 'homing'), (1024, 'homed'), (2048,
'initializing'), (4096, 'tracking'), (8192, 'settled'), (16384, 'motion_error'),
(32768, 'instr_error'), (65536, 'interlock'), (131072, 'overtemp'), (262144,
'volt_supply_fault'), (524288, 'commutation_error'), (1048576, 'digio1'), (2097152,
'digio2'), (4194304, 'digio3'), (8388608, 'digio4'), (16777216, 'current_limit'),
(33554432, 'encoder_fault'), (67108864, 'overcurrent'), (134217728,
'curr_supply_fault'), (268435456, 'power_ok'), (536870912, 'active'), (1073741824,
'error'), (2147483648, 'enabled')]
```

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_channel**(*channel*)

Context manager for temporarily using a different default channel

**class** `pylablib.devices.Thorlabs.kinesis.TQuadDetectorPIDParams`(*p*, *i*, *d*)

Bases: `tuple`

**d**

**i**

**p**

**class** pylablib.devices.Thorlabs.kinesis.TQuadDetectorSetpoint(*xpos, ypos*)

Bases: `tuple`

**xpos**

**ypos**

**class** pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings(*xdiff, ydiff, sum, xpos, ypos*)

Bases: `tuple`

**sum**

**xdiff**

**xpos**

**ydiff**

**ypos**

**class** pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams(*xmin, xmax, ymin, ymax, xgain, ygain, route, open\_loop\_out*)

Bases: `tuple`

**open\_loop\_out**

**route**

**xgain**

**xmax**

**xmin**

**ygain**

**ymax**

**ymin**

**class** pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector(*conn, timeout=3.0*)

Bases: `BasicKinesisDevice`

Kinesis quadrature detectors: KPA101, TPA101, TQD001.

Implements FTDI chip connectivity via pyft232 (virtual serial interface).

**Parameters**

**conn** (*str*) – serial connection parameters (usually an 8-digit device serial number).

**get\_pid\_parameters()**

Get current PID gain parameters (p, i, d)

**set\_pid\_parameters**(*p=None, i=None, d=None*)

Set current PID gain parameters (*p*, *i*, *d*).

If any parameter is *None*, use the current value.

**get\_manual\_output**()

Get current manual output values (*xpos*, *ypos*) (used in open loop mode)

**set\_manual\_output**(*xpos=None, ypos=None*)

Set current manual output values (used in open loop mode).

If any parameter is *None*, use the current value.

**get\_readings**()

Get current readings (*xdiff*, *ydiff*, *sum*, *xpos*, *ypos*)

**get\_operation\_mode**()

Get current operation mode: "monitor", "open\_loop", "closed\_loop", or "auto\_loop"

**set\_operation\_mode**(*mode*)

Set current operation mode: "monitor", "open\_loop", "closed\_loop", or "auto\_loop"

**get\_output\_parameters**()

Get current output parameters (*xmin*, *xmax*, *ymin*, *ymax*, *xgain*, *ygain*, *route*, *open\_loop\_out*)

**set\_output\_parameters**(*xmin=None, xmax=None, ymin=None, ymax=None, xgain=None, ygain=None, route=None, open\_loop\_out=None*)

Set current PID gain parameters (*xmin*, *xmax*, *ymin*, *ymax*, *xgain*, *ygain*, *route*, *open\_loop\_out*).

*xmin*, *xmax*, *ymin*, and *ymax* specify output limits, *xgain* and *ygain* specify additional separate gain (between -1 and 1), *route* sets where output is routed in the closed loop mode (either "sma\_only" or "sma\_hub"), *open\_loop\_out* specifies the output source in the open loop mode (either "zero" or "fixed"). If any parameter is *None*, use the current value.

## Error

alias of [\*ThorlabsError\*](#)

**add\_background\_comm**(*messageID*)

Mark given *messageID* as a 'background' message, which can be sent at any point without prompt (e.g., some operation confirmation).

If it is received instead during *recv\_comm* operations, it is ignored, and the corresponding counter is increased.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**blink**(*channel=1, dest='host'*)

Identify the physical device (by, e.g., blinking status LED or screen)

**check\_background\_comm**(*messageID*)

Return message counter and the last message value (*None* if not message received yet) of a given 'background' message

**close()**

Close the backend

**flush\_comm**(*nmax=1000*)

Flush any commands in the queue.

if *nmax* is not `None`, it specifies the maximal number of commands to flush.

**get\_device\_info**(*dest='host'*)

Get device info.

Return tuple (*serial\_no*, *model\_no*, *fw\_ver*, *hw\_type*, *hw\_ver*, *mod\_state*, *nchannels*, *notes*).

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_number\_of\_channels**()

Get number of channels on the device

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**static list\_devices**(*filter\_ids=True*)

List all connected devices.

Return list of tuples (*conn*, *description*). If *filter\_ids==True*, only leave devices with Thorlabs-like IDs (8-digit numbers). Otherwise, show all devices (some of them might not be Thorlabs-related).

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**query**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host', *replyID*=-1, *flush*='auto')

Send a query to the device and receive the reply.

A combination of [send\\_comm\(\)](#) and [recv\\_comm\(\)](#). If *replyID* is not None, specifies the expected reply message ID; if -1 (default), set to be *messageID*+1 (the standard convention). *flush* specifies whether input queue will be flushed before reading; "auto" means that it will be flushed if the expected reply is among the background messages, i.e., it could be already present in the queue.

**recv\_comm**(*expected\_id*=None, *timeout*=None)

Receive a message.

Return either [BasicKinesisDevice.CommShort](#) or [BasicKinesisDevice.CommData](#) depending on the message type (fixed length with two parameters, or variable length with associated data). If *expected\_id* is not None and the received message ID is different from *expected\_id*, raise an error. If *timeout* is not None, it can specify the timeout to read the command header (the rest is done with the usual timeout). For details, see APT communications protocol.

**send\_comm**(*messageID*, *param1*=0, *param2*=0, *source*=1, *dest*='host')

Send a message with no associated data.

For details, see APT communications protocol.

**send\_comm\_data**(*messageID*, *data*, *source*=1, *dest*='host')

Send a message with associated data.

For details, see APT communications protocol.

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## pylablib.devices.Thorlabs.misc module

**class** pylablib.devices.Thorlabs.misc.**TPMDeviceInfo**(*manufacturer*, *name*, *serial*, *firmware*)

Bases: [tuple](#)

**firmware**

**manufacturer**

**name**

**serial**

**class** pylablib.devices.Thorlabs.misc.**TPMSensorInfo**(*name*, *serial*, *calibration*, *type*, *subtype*, *flags*)

Bases: [tuple](#)

**calibration**

**flags**

**name**

**serial**

**subtype**

**type**

**class** `pylablib.devices.Thorlabs.misc.GenericPM(addr)`

Bases: [\*SCPIDevice\*](#)

Generic Thorlabs optical Power Meter.

**Parameters**

**addr** – connection address (usually, a VISA connection string or a COM port for bluetooth devices)

**Error**

alias of [\*ThorlabsError\*](#)

**ReraiseError**

alias of [\*ThorlabsBackendError\*](#)

**open()**

Open the backend

**get\_device\_info()**

Get device info.

Return tuple (manufacturer, name, serial, firmware).

**get\_sensor\_info()**

Get sensor info.

Return tuple (name, serial, calibration, type, subtype, flags). For devices with integrated sensors (e.g., PM160) the sensor name is the same as the device name.

**update\_sensor\_modes()**

Update the list of supported sensor modes (only makes sense if the sensor has been changed since the connection was opened)

**get\_supported\_sensor\_modes()**

Get a list of supported sensor modes.

Can contain "power", "energy", "voltage", "current", or "frequency".

**get\_sensor\_mode()**

Get current sensor mode.

Can be "power", "energy", "voltage", "current", or "frequency".

**set\_sensor\_mode(sensor\_mode='power')**

Set current sensor mode.

Can be one of the modes returned by [\*get\\_supported\\_sensor\\_modes\(\)\*](#).

**is\_autorange\_enabled(sensor\_mode=None)**

Check if autorange is enabled for the given sensor mode.

If *sensor\_mode* is *None*, return value for the current sensor mode.

**enable\_autorange(enable=True, sensor\_mode=None)**

Enable or disable autorange for the given sensor mode.

If *sensor\_mode* is *None*, set value for the current sensor mode.

**get\_range**(*sensor\_mode=None*)

Get measurement range for the given sensor mode.

If *sensor\_mode* is *None*, return value for the current sensor mode.

**set\_range**(*rng=None, sensor\_mode=None*)

Set measurement range for the given sensor mode.

If *rng* is *None* or "full", set the maximal range. If *sensor\_mode* is *None*, return value for the current sensor mode.

**get\_wavelength**()

Get current wavelength (in nm)

**get\_wavelength\_range**()

Get available wavelength range (in nm)

**set\_wavelength**(*wavelength*)

Set current wavelength (in nm)

**get\_reading**(*sensor\_mode=None, measure=True, overrng='keep'*)

Get the reading in a given mode.

If *sensor\_mode* is *None*, return reading in the currently set up mode (*get\_sensor\_mode()*); otherwise, set the sensor mode to the requested one. If *measure==True*, initiate a new measurement; otherwise, return the last measured value. *overrng* describes behavior if the power readings are outside of the current range; can be "keep" (keep the default device behavior, which returns a very large number, about 9.9E37), "error" (raise an error), or "max" (trim to the maximal value for the current range).

**get\_power**()

Measure and return the optical power

**BackendError**

alias of *DeviceBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo==True*, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**flush**(*one\_line=False*)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout=None*)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id**(*timeout=None*)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes).



If `include_header==True`, return the data with the header; otherwise, return only the content. If `flush_term==True`, flush the following line to skip terminator characters after the binary data, which are added by some devices. `timeout` overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If `new_instrument==True`, create a new backend instance. If `ignore_error==True`, ignore errors on closing.

**reset**()

Reset the device (by default, `"*RST"` command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive `write()` operations are bundled together with `;` delimiter. The actual write is performed at the `read()/ask()` operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either `'sync'` (perform `wait_sync()`), `'dev'` (perform `wait_dev()`) or `'none'` (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with `" , "`.
- **arg\_type** (*str*) – Argument type. Can be `'raw'` (in which case data is sent raw), `'string'`, `'int'`, `'float'`, `'bool'`, a format string (such as `'{: .3f}'`) or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'`

with `arg=[1,2]` will produce a string `'1;2'`); if a list of types is used, each element of `arg` is converted using the corresponding type, and the result is joined with `", "`.

- **unit** (*str*) – If not `None`, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (`false_value`, `true_value`) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if `True`, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if `None`, use the class default `._default_write_sync` attribute (`False` by default).
- **read\_echo** (*bool*) – If `True`, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.Thorlabs.misc.PM160(addr)`

Bases: [\*GenericPM\*](#)

Thorlabs PM160 optical Power Meter.

#### Parameters

**addr** – connection address (usually, a VISA connection string or a COM port for bluetooth devices)

#### BackendError

alias of [\*DeviceBackendError\*](#)

#### Error

alias of [\*ThorlabsError\*](#)

#### ReraiseError

alias of [\*ThorlabsBackendError\*](#)

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {`name:` `value`} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [\*read\(\)\*](#). If `read_echo==True`, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**enable\_autorange**(*enable*=True, *sensor\_mode*=None)

Enable or disable autorange for the given sensor mode.

If *sensor\_mode* is `None`, set value for the current sensor mode.

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If `one_line==True`, read only a single line.

**static get\_arg\_type(*arg*)**

Autodetect argument type

**get\_device\_info()**

Get device info.

Return tuple (manufacturer, name, serial, firmware).

**get\_device\_variable(*key*)**

Get the value of a settings, status, or full info parameter

**get\_esr(*timeout=None*)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(*include=0*)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(*include=0*)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_id(*timeout=None*)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_power()**

Measure and return the optical power

**get\_range(*sensor\_mode=None*)**

Get measurement range for the given sensor mode.

If *sensor\_mode* is *None*, return value for the current sensor mode.

**get\_reading(*sensor\_mode=None, measure=True, overrng='keep'*)**

Get the reading in a given mode.

If *sensor\_mode* is *None*, return reading in the currently set up mode (*get\_sensor\_mode()*); otherwise, set the sensor mode to the requested one. If *measure==True*, initiate a new measurement; otherwise, return the last measured value. *overrng* describes behavior if the power readings are outside of the current range; can be "keep" (keep the default device behavior, which returns a very large number, about 9.9E37), "error" (raise an error), or "max" (trim to the maximal value for the current range).

**get\_sensor\_info()**

Get sensor info.

Return tuple (name, serial, calibration, type, subtype, flags). For devices with integrated sensors (e.g., PM160) the sensor name is the same as the device name.

**get\_sensor\_mode()**

Get current sensor mode.

Can be "power", "energy", "voltage", "current", or "frequency".

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_supported\_sensor\_modes**()

Get a list of supported sensor modes.

Can contain "power", "energy", "voltage", "current", or "frequency".

**get\_wavelength**()

Get current wavelength (in nm)

**get\_wavelength\_range**()

Get available wavelength range (in nm)

**is\_autorange\_enabled**(*sensor\_mode=None*)

Check if autorange is enabled for the given sensor mode.

If *sensor\_mode* is *None*, return value for the current sensor mode.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is *DataFormat* description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If

`flush_term==True`, flush the following line to skip terminator characters after the binary data, which are added by some devices. `timeout` overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If `new_instrument==True`, create a new backend instance. If `ignore_error==True`, ignore errors on closing.

**reset**()

Reset the device (by default, `"*RST"` command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_range**(*rng=None, sensor\_mode=None*)

Set measurement range for the given sensor mode.

If `rng` is `None` or `"full"`, set the maximal range. If `sensor_mode` is `None`, return value for the current sensor mode.

**set\_sensor\_mode**(*sensor\_mode='power'*)

Set current sensor mode.

Can be one of the modes returned by [get\\_supported\\_sensor\\_modes\(\)](#).

**set\_wavelength**(*wavelength*)

Set current wavelength (in nm)

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**update\_sensor\_modes**()

Update the list of supported sensor modes (only makes sense if the sensor has been changed since the connection was opened)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with `;` delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either `'sync'` (perform [wait\\_sync\(\)](#)), `'dev'` (perform [wait\\_dev\(\)](#)) or `'none'` (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

```
write(msg, arg=None, arg_type=None, unit=None, bool_selector=None, wait_sync=None,  
      read_echo=False, read_echo_delay=0.0)
```

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., **arg\_type**='{0};{1}' with **arg**=[1,2] will produce a string '1;2'); if a list of types is used, each element of **arg** is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (false\_value, true\_value) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

### pylablib.devices.Thorlabs.serial module

```
class pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface(conn)
```

Bases: *SCPIDevice*

Generic Thorlabs device interface using Serial communication.

#### Parameters

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

#### Error

alias of *ThorlabsError*

#### ReraiseError

alias of *ThorlabsBackendError*

#### open()

Open the backend

#### BackendError

alias of *DeviceBackendError*

#### apply\_settings(settings)

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout*=None)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include*=0)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status**(*include*=0)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id**(*timeout*=None)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include*=0)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened**()

Check if the device is connected

**lock**(*timeout*=None)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout*=None)

Context manager for lock & unlock

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform [wait\\_sync\(\)](#)), 'dev' (perform [wait\\_dev\(\)](#)) or 'none' (do nothing).



**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., *arg\_type*='{0};{1}' with *arg*=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (false\_value, true\_value) of two strings to represent bool argument; by default, use *.\_bool\_selector* attribute.
- **wait\_sync** – if True, append the sync command (specified as *.\_wait\_sync\_comm* attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default *.\_default\_write\_sync* attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if *read\_echo*==True.

**class** `pylablib.devices.Thorlabs.serial.FW`(*conn, respect\_bound=True*)

Bases: [\*ThorlabsSerialInterface\*](#)

Thorlabs FW102/212 motorized filter wheels.

**Parameters**

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **respect\_bound** (*bool*) – if True, avoid crossing the boundary between the first and the last position in the wheel

**ask**(*msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False*)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [\*read\(\)\*](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**get\_position()**

Get the wheel position (starting from 1)

**set\_position(*pos*)**

Set the wheel position (starting from 1)

**get\_pcount()**

Get the number of wheel positions (6 or 12)

**set\_pcount(*pcount*)**

Set the number of wheel positions (6 or 12)

**get\_speed\_mode()**

Get the motion speed mode ("low" or "high")

**set\_speed\_mode(*speed\_mode*)**

Set the motion speed mode ("low" or "high")

**get\_trigger\_mode()**

Get the trigger mode ("in" to input external trigger, "out" to output trigger)

**set\_trigger\_mode(*trigger\_mode*)**

Set the trigger mode ("in" to input external trigger, "out" to output trigger)

**get\_sensor\_mode()**

Get the sensor mode ("off" to turn off when idle to eliminate stray light, "on" to remain on)

**set\_sensor\_mode(*sensor\_mode*)**

Set the sensor mode ("off" to turn off when idle to eliminate stray light, "on" to remain on)

**store\_settings()**

Store current settings as default

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *ThorlabsError*

**ReraiseError**

alias of *ThorlabsBackendError*

**apply\_settings(*settings*)**

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**close()**

Close the backend

**flush(*one\_line=False*)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line==True*, read only a single line.

**static get\_arg\_type(*arg*)**

Autodetect argument type

**get\_device\_variable**(key)

Get the value of a settings, status, or full info parameter

**get\_esr**(timeout=None)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(include=0)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status**(include=0)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id**(timeout=None)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(include=0)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened**()

Check if the device is connected

**lock**(timeout=None)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(timeout=None)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(data, fmt, include\_header=False)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header*==True, the data is assumed to be in a (somewhat) standard SCPI format: b'#', then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header*==False), assume that the header is already removed.

**read**(data\_type='string', timeout=None)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive *write()* operations are bundled together with ; delimiter. The actual write is performed at the *read()/ask()* operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform *wait\_sync()*), 'dev' (perform *wait\_dev()*) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".

- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., `arg_type='{0};{1}'` with `arg=[1,2]` will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ",".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

**class** `pylablib.devices.Thorlabs.serial.FWv1(conn, pcount=6, respect_bound=True)`

Bases: [\*ThorlabsSerialInterface\*](#)

Thorlabs FW102/212 v1.0 (older version) motorized filter wheels.

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **pcount** – number of positions in the wheel
- **respect\_bound** (*bool*) – if True, avoid crossing the boundary between the first and the last position in the wheel

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [`read\(\)`](#). If `read_echo==True`, assume that the device first echoes the input and skip it.

**get\_position()**

Get the wheel position (starting from 1)

**set\_position**(*pos*)

Set the wheel position (starting from 1)

**get\_pcount()**

Get the number of wheel positions (6 or 12)

**get\_trigger\_mode()**

Get the trigger mode ("in" to input external trigger, "out" to output trigger)

**set\_trigger\_mode**(*trigger\_mode*)

Set the trigger mode ("in" to input external trigger, "out" to output trigger)

**BackendError**

alias of [\*DeviceBackendError\*](#)

**Error**

alias of *ThorlabsError*

**ReraiseError**

alias of *ThorlabsBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**close()**

Close the backend

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**open()**

Open the backend

**static parse\_array\_data**(*data*, *fmt*, *include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string'*, *timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False*, *timeout=None*, *flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True*, *ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset()**

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer()**

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform [wait\\_sync\(\)](#)), 'dev' (perform [wait\\_dev\(\)](#)) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., *arg\_type*='{0};{1}' with *arg*=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (false\_value, true\_value) of two strings to represent bool argument; by default, use *.\_bool\_selector* attribute.
- **wait\_sync** – if True, append the sync command (specified as *.\_wait\_sync\_comm* attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default *.\_default\_write\_sync* attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if *read\_echo*==True.

**class** pylablib.devices.Thorlabs.serial.MDT69xA(*conn*)

Bases: *ThorlabsSerialInterface*

Thorlabs MDT693A/4A high-voltage source.

Uses MDT693A program interface, so should be compatible with both A and B versions (though it doesn't support all functions of MDT693B/4B)

**Parameters**

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

**get\_voltage**(*channel='x'*)

Get the output voltage in Volts at a given channel

**set\_voltage**(*voltage, channel='x'*)

Set the output voltage in Volts at a given channel



**get\_voltage\_range()**

Get the selected voltage range in Volts (75, 100 or 150)

**BackendError**

alias of *DeviceBackendError*

**Error**

alias of *ThorlabsError*

**ReraiseError**

alias of *ThorlabsBackendError*

**apply\_settings(settings)**

Apply the settings.

*settings* is a dict {*name*: *value*} of the available device settings. Non-applicable settings are ignored.

**ask(msg, data\_type='string', delay=0.0, timeout=None, read\_echo=False)**

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in *read()*. If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close()**

Close the backend

**flush(one\_line=False)**

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type(arg)**

Autodetect argument type

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_esr(timeout=None)**

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info(include=0)**

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status(include=0)**

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id(timeout=None)**

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data, fmt, include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: *b'#'*, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string', timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False, timeout=None, flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True, ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive **write**() operations are bundled together with ; delimiter. The actual write is performed at the **read**()/**ask**() operation or at the end of the block.

**wait**(*wait\_type='sync', timeout=None, wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform **wait\_sync**()), 'dev' (perform **wait\_dev**()) or 'none' (do nothing).

**wait\_dev**()

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

#### Parameters

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{: .3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., **arg\_type**='{0};{1}' with **arg**=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use `._bool_selector` attribute.
- **wait\_sync** – if True, append the sync command (specified as `._wait_sync_comm` attribute, `"*OPC?"` by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default `._default_write_sync` attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if `read_echo==True`.

## Module contents

### pylablib.devices.Toptica package

#### Submodules

#### pylablib.devices.Toptica.base module

**exception** pylablib.devices.Toptica.base.**TopticaError**

Bases: *DeviceError*

Generic Toptica device error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Toptica.base.**TopticaBackendError**(*exc*)

Bases: *TopticaError*, *DeviceBackendError*

Toptica backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

#### pylablib.devices.Toptica.ibeam module

pylablib.devices.Toptica.ibeam.**muxchan**(\*args, \*\*kwargs)

Multiplex the function over its addr argument

**class** pylablib.devices.Toptica.ibeam.**TDeviceInfo**(*serial*, *version*)

Bases: *tuple*

**serial**

**version**

**class** pylablib.devices.Toptica.ibeam.**TWorkHours**(*power\_up*, *laser\_on*)

Bases: *tuple*

**laser\_on**

**power\_up**

**class** pylablib.devices.Toptica.ibeam.**TTemperatures**(*diode*, *baseplate*)

Bases: *tuple*

**baseplate**

**diode**

**class** `pylablib.devices.Toptica.ibeam.TopticalBeam`(*conn*='COM1')

Bases: *ICommBackendWrapper*

Toptica iBeam smart laser controller.

#### Parameters

- **conn** – connection parameters - index of the Attocube ANC350 in the system (for a single controller leave 0)
- **timeout** (*float*) – default operation timeout

#### Error

alias of *TopticaError*

#### `open()`

Open the backend

**query**(*comm*, *multiline*=False, *keep\_whitespace*=False, *check\_error*='FEW', *reply*=True)

#### `reboot()`

Reboot the laser system

#### `get_device_info()`

Get the device info of the laser system: (*serial*, *version*)

#### `get_full_data`(*formatted*=False)

Return the comprehensive device data

#### `get_work_hours()`

Get the work hours (power on time and laser on time)

#### `get_channels_number()`

Get number of supported laser channels

#### `is_enabled()`

Check if the output is enabled

#### `enable`(*enabled*=True)

Turn the output on or off

#### `is_channel_enabled`(*channel*='all')

Check if the specific channel is enabled

#### `enable_channel`(*channel*, *enabled*=True)

Turn the specific channel on or off

#### `get_channel_power`(*channel*='all')

Get specified channel power (in W)

#### `set_channel_power`(*channel*, *power*)

Set channel power (in W)

#### `get_output_power()`

Get current output power (in W)

**get\_drive\_current()**

Get current diode drive current (in A)

**get\_current\_limits()**

Get settings of all current limits (in A) as a dictionary

**get\_temperatures()**

Get settings of all current limits (in A) as a dictionary

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**lock(timeout=None)**

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking(timeout=None)**

Context manager for lock & unlock

**set\_device\_variable(key, value)**

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Trinamic package

#### Submodules

#### pylablib.devices.Trinamic.base module

**exception** pylablib.devices.Trinamic.base.**TrinamicError**

Bases: *DeviceError*

Generic Trinamic error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Trinamic.base.**TrinamicBackendError**(*exc*)

Bases: *TrinamicError*, *DeviceBackendError*

Generic Trinamic backend communication error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** pylablib.devices.Trinamic.base.**TrinamicTimeoutError**

Bases: *TrinamicError*

Generic Trinamic timeout error

**add\_note()**

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback()**

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.Trinamic.base.**TLimitSwitchParams**(*left\_enable*, *right\_enable*)

Bases: *tuple*

**left\_enable**

**right\_enable**

**class** pylablib.devices.Trinamic.base.**TVelocityParams**(*speed*, *accel*, *pulse\_divisor*, *ramp\_divisor*)

Bases: *tuple*

**accel**

**pulse\_divisor**

**ramp\_divisor**

**speed**

**class** pylablib.devices.Trinamic.base.**THomeParams**(*mode, search\_speed, switch\_speed*)

Bases: [tuple](#)

**mode**

**search\_speed**

**switch\_speed**

**class** pylablib.devices.Trinamic.base.**TMCM1110ReplyData**(*comm, status, value, addr, module*)

Bases: [tuple](#)

**addr**

**comm**

**module**

**status**

**value**

**class** pylablib.devices.Trinamic.base.**TMCM1110**(*conn*)

Bases: [ICommBackendWrapper](#), [IStage](#)

Trinamic stepper motor controller TMCM-1110 controlled using TMCL Firmware.

#### Parameters

**conn** – serial connection parameters (usually port or a tuple containing port and baudrate)

#### Error

alias of [TrinamicError](#)

#### open()

Open the backend

**query**(*comm, comm\_type, value, result\_format='i', bank=0, addr=0*)

Send a query to the stage and return the reply.

For details, see TMCM-1110 firmware manual.

**get\_axis\_parameter**(*parameter, result\_format='i', axis=0, addr=0*)

Get a given axis parameter at the given axis and device address

**set\_axis\_parameter**(*parameter, value, axis=0, addr=0*)

Set a given axis parameter at the given axis and device address (volatile; resets on power cycling)

**store\_axis\_parameter**(*parameter, value=None, axis=0, addr=0*)

Store a given axis parameter in EEPROM at the given axis and device address (by default, value is the current value)



**get\_global\_parameter**(*parameter*, *result\_format='i'*, *bank=0*, *addr=0*)

Get a given global parameter

**set\_global\_parameter**(*parameter*, *value*, *bank=0*, *addr=0*)

Set a given global parameter

**get\_general\_input**(*port=0*, *bank=0*, *addr=0*)

Get value of an input at a given bank (0-2) and port.

Bank 0 is digital input (7 ports), bank 1 is analog input (1 port, value from 0 to  $2^{16}-1$ ), bank 2 is digital output (8 ports). For port assignments, see TMCM-1110 firmware manual.

**set\_general\_output**(*value*, *port=0*, *bank=2*, *addr=0*)

Set value of a digital input at a given bank (only bank 2 is available) and port.

For port assignments, see TMCM-1110 firmware manual.

**move\_to**(*position*, *axis=0*, *addr=0*)

Move to a given position

**move\_by**(*steps=1*, *axis=0*, *addr=0*)

Move by a given number of steps

**get\_position**(*axis=0*, *addr=0*)

Get the current axis position

**set\_position\_reference**(*pos=0*, *axis=0*, *addr=0*)

Set the current axis position as a reference (the actual motor position stays the same)

**jog**(*direction*, *speed=None*, *axis=0*, *addr=0*)

Jog in a given direction with a given speed.

*direction* can be either "-" (negative, left) or "+" (positive, right). The motion continues until it is explicitly stopped, or until a limit is hit. If *speed* is *None*, use the standard speed value.

**stop**(*axis=0*, *addr=0*)

Stop motion

**get\_microstep\_resolution**(*axis=0*, *addr=0*)

Get the number of microsteps per full step (always a power of 2)

**set\_microstep\_resolution**(*resolution*, *axis=0*, *addr=0*)

Set the number of microsteps per full step (rounded to a nearest power of 2)

**get\_current\_parameters**(*max\_current=1*, *axis=0*, *addr=0*)

Return diving current parameter (*drive\_current*, *standby\_current*).

*drive\_current* is the maximal drive current, which is given as a fraction of the *max\_current* (which is either 1A or 2.8A depending on the hardware jumper). *standby\_current* is given as a fraction of *drive\_current*.

**setup\_current**(*drive\_current=None*, *standby\_current=None*, *max\_current=1.0*, *axis=0*, *addr=0*)

Set drive and standby currents.

WARNING: too high of a setting might damage the motor. *drive\_current* is the maximal drive current, which is given as a fraction of the *max\_current* (which is either 1A or 2.8A depending on the hardware jumper, as described in the hardware manual). *standby\_current* is given as a fraction of *drive\_current*. Any *None* parameters are left unchanged.

**get\_limit\_switches\_parameters**(*axis=0, addr=0*)

Return limit switch parameters (*left\_enable, right\_enable*)

**setup\_limit\_switches**(*left\_enable=None, right\_enable=None, axis=0, addr=0*)

Setup limit switch parameters

**get\_limit\_switches\_state**(*axis=0, addr=0*)

Get the state of the left and right limit switches

**get\_switch\_polarity**(*axis=0, addr=0*)

Get end switch polarity (False for normal, True for reversed).

Note that for 3-axis controller (TMCM-3110) the polarity is the same for all axes, and for 6-axis controller (TMCM-6110) it has to be the same for the first 3 and the last 3 axes

**set\_switch\_polarity**(*polarity=False, axis=0, addr=0*)

Set end switch polarity (False for normal, True for reversed).

Note that for 3-axis controller (TMCM-3110) the polarity is the same for all axes, and for 6-axis controller (TMCM-6110) it has to be the same for the first 3 and the last 3 axes

**get\_home\_parameters**(*axis=0, addr=0*)

Return homing parameters (*mode, search\_speed, switch\_speed*).

*mode* is one of 16 different values, which can start with "lim\_" indicating reliance on limit switches, or with "home\_" indicating usage of home switches. Home-based switches can also be inverted (with "\_inv" in the end), indicating that the homing switch function is inverted (0 instead of 1 means that the switch is engaged). More details can be found in the manual. *search\_speed* and *switch\_speed* describe, respectively, the initial speed while searching for the switch, and the final homing speed while searching for the edge of the switch action. Both are given in *internal* units.

**setup\_home**(*home\_mode=None, search\_speed=None, switch\_speed=None, axis=0, addr=0*)

Setup homing parameters (*mode, search\_speed, switch\_speed*).

*mode* is one of 16 different values, which can start with "lim\_" indicating reliance on limit switches, or with "home\_" indicating usage of home switches. Home-based switches can also be inverted (with "\_inv" in the end), indicating that the homing switch function is inverted (0 instead of 1 means that the switch is engaged). More details can be found in the manual. *search\_speed* and *switch\_speed* describe, respectively, the initial speed while searching for the switch, and the final homing speed while searching for the edge of the switch action. Both are given in *internal* units.

**home**(*wait=True, timeout=30.0, axis=0, addr=0*)

Home the given axis.

If *wait==True*, wait until the homing is complete or until *timeout* is passed. Note that homing affects the velocity parameters, which need to be re-established after the homing is complete. This is done automatically when *wait==True*, but needs to be done manually otherwise.

**is\_homing**(*axis=0, addr=0*)

Check if homing is in progress at the given address

**get\_last\_home\_position**(*axis=0, addr=0*)

Get the last readout position when the homing operation was complete (0 upon startup)

**get\_velocity\_parameters**(*axis=0, addr=0*)

Return velocity parameters (*speed, accel, pulse\_divisor, ramp\_divisor*).

*speed* and *accel* denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in *internal* units. *pulse\_divisor* is the driver pulse divisor, which defines how internal velocity units

translate into microsteps/s (see `get_velocity_factor()`); can only be a power of 2, higher values mean slower motion. `ramp_divisor` is the driver ramp divisor, which, together with the pulse divisor, defines how internal acceleration units translate into microsteps/s<sup>2</sup> (see `get_acceleration_factor()`); rounded to the nearest power of 2, higher values mean slower acceleration.

**setup\_velocity**(*speed=None, accel=None, pulse\_divisor=None, ramp\_divisor=None, axis=0, addr=0*)

Setup velocity parameters (`speed`, `accel`, `pulse_divisor`, `ramp_divisor`).

`speed` and `accel` denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in *internal* units. `pulse_divisor` is the driver pulse divisor, which defines how internal velocity units translate into microsteps/s (see `get_velocity_factor()`); rounded to the nearest power of 2, higher values mean slower motion. `ramp_divisor` is the driver ramp divisor, which, together with the pulse divisor, defines how internal acceleration units translate into microsteps/s<sup>2</sup> (see `get_acceleration_factor()`); rounded to the nearest power of 2, higher values mean slower acceleration. `None` values are left unchanged.

**get\_velocity\_factor**(*axis=0, addr=0*)

Get the ratio between the real speed (in microsteps/s) and the internal units

**get\_acceleration\_factor**(*axis=0, addr=0*)

Get the ratio between the real acceleration (in microsteps/s<sup>2</sup>) and the internal units

**get\_current\_speed**(*axis=0, addr=0*)

Get the instantaneous speed in internal units

**is\_moving**(*axis=0, addr=0*)

Check if the motor is moving

**wait\_move**(*axis=0, addr=0*)

Wait until motion is done

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings**(*include=0*)

Get dict {`name`: `value`} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**is\_opened()**

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock()**

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**class** `pylablib.devices.Trinamic.base.TMCMx110`(*conn, naxes=None*)

Bases: `TMCM1110`, `IMultiaxisStage`

Trinamic multi-axis stepper motor controller TMCM-x110 (1110, 3110, 6110) controlled using TMCL Firmware.

The main difference from the single-axis TMCM1110 is that it determines the number of axes upon the connection, and that the device variables return dictionaries `{axis: value}` instead of a single value (even for single-axis controller for consistency).

#### Parameters

- **conn** – serial connection parameters (usually port or a tuple containing port and baudrate)
- **naxes** – maximal number of axes to check for upon connection; if the actual number is larger, use only first *naxes* axes

#### Error

alias of `TrinamicError`

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict `{name: value}` of the device available settings. Non-applicable settings are ignored.

**close()**

Close the backend

**get\_acceleration\_factor**(*axis=0, addr=0*)

Get the ratio between the real acceleration (in microsteps/s<sup>2</sup>) and the internal units

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**get\_axis\_parameter**(*parameter, result\_format='i', axis=0, addr=0*)

Get a given axis parameter at the given axis and device address

**get\_current\_parameters**(*max\_current=1, axis=0, addr=0*)

Return diving current parameter (`drive_current`, `standby_current`).

`drive_current` is the maximal drive current, which is given as a fraction of the *max\_current* (which is either 1A or 2.8A depending on the hardware jumper). `standby_current` is given as a fraction of `drive_current`.

**get\_current\_speed**(*axis=0, addr=0*)

Get the instantaneous speed in internal units

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_general\_input**(*port=0, bank=0, addr=0*)

Get value of an input at a given bank (0-2) and port.

Bank 0 is digital input (7 ports), bank 1 is analog input (1 port, value from 0 to 2\*16-1), bank 2 is digital output (8 ports). For port assignments, see TMC1110 firmware manual.

**get\_global\_parameter**(*parameter, result\_format='i', bank=0, addr=0*)

Get a given global parameter

**get\_home\_parameters**(*axis=0, addr=0*)

Return homing parameters (*mode, search\_speed, switch\_speed*).

*mode* is one of 16 different values, which can start with "lim\_" indicating reliance on limit switches, or with "home\_" indicating usage of home switches. Home-based switches can also be inverted (with "\_inv" in the end), indicating that the homing switch function is inverted (0 instead of 1 means that the switch is engaged). More details can be found in the manual. *search\_speed* and *switch\_speed* describe, respectively, the initial speed while searching for the switch, and the final homing speed while searching for the edge of the switch action. Both are given in *internal* units.

**get\_last\_home\_position**(*axis=0, addr=0*)

Get the last readout position when the homing operation was complete (0 upon startup)

**get\_limit\_switches\_parameters**(*axis=0, addr=0*)

Return limit switch parameters (*left\_enable, right\_enable*)

**get\_limit\_switches\_state**(*axis=0, addr=0*)

Get the state of the left and right limit switches

**get\_microstep\_resolution**(*axis=0, addr=0*)

Get the number of microsteps per full step (always a power of 2)

**get\_position**(*axis=0, addr=0*)

Get the current axis position

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_switch\_polarity**(*axis=0, addr=0*)

Get end switch polarity (False for normal, True for reversed).

Note that for 3-axis controller (TMCM-3110) the polarity is the same for all axes, and for 6-axis controller (TMCM-6110) it has to be the same for the first 3 and the last 3 axes

**get\_velocity\_factor**(*axis=0, addr=0*)

Get the ratio between the real speed (in microsteps/s) and the internal units

**get\_velocity\_parameters**(*axis=0, addr=0*)

Return velocity parameters (speed, accel, pulse\_divisor, ramp\_divisor).

speed and accel denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in *internal* units. pulse\_divisor is the driver pulse divisor, which defines how internal velocity units translate into microsteps/s (see [get\\_velocity\\_factor\(\)](#)); can only be a power of 2, higher values mean slower motion. ramp\_divisor is the driver ramp divisor, which, together with the pulse divisor, defines how internal acceleration units translate into microsteps/s<sup>2</sup> (see [get\\_acceleration\\_factor\(\)](#)); rounded to the nearest power of 2, higher values mean slower acceleration.

**home**(*wait=True, timeout=30.0, axis=0, addr=0*)

Home the given axis.

If *wait==True*, wait until the homing is complete or until *timeout* is passed. Note that homing affects the velocity parameters, which need to be re-established after the homing is complete. This is done automatically when *wait==True*, but needs to be done manually otherwise.

**is\_homing**(*axis=0, addr=0*)

Check if homing is in progress at the given address

**is\_moving**(*axis=0, addr=0*)

Check if the motor is moving

**is\_opened**()

Check if the device is connected

**jog**(*direction, speed=None, axis=0, addr=0*)

Jog in a given direction with a given speed.

*direction* can be either "-" (negative, left) or "+" (positive, right). The motion continues until it is explicitly stopped, or until a limit is hit. If *speed* is *None*, use the standard speed value.

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**move\_by**(*steps=1, axis=0, addr=0*)

Move by a given number of steps

**move\_to**(*position, axis=0, addr=0*)

Move to a given position

**open**()

Open the backend

**query**(*comm, comm\_type, value, result\_format='i', bank=0, addr=0*)

Send a query to the stage and return the reply.

For details, see TMCM-1110 firmware manual.

**remap\_axes**(*mapping*, *accept\_original=True*)

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by [get\\_all\\_axes\(\)](#)), or a dictionary {*alias*: *original*} of the new axes aliases.

**set\_axis\_parameter**(*parameter*, *value*, *axis=0*, *addr=0*)

Set a given axis parameter at the given axis and device address (volatile; resets on power cycling)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**set\_general\_output**(*value*, *port=0*, *bank=2*, *addr=0*)

Set value of a digital input at a given bank (only bank 2 is available) and port.

For port assignments, see TMCM-1110 firmware manual.

**set\_global\_parameter**(*parameter*, *value*, *bank=0*, *addr=0*)

Set a given global parameter

**set\_microstep\_resolution**(*resolution*, *axis=0*, *addr=0*)

Set the number of microsteps per full step (rounded to a nearest power of 2)

**set\_position\_reference**(*pos=0*, *axis=0*, *addr=0*)

Set the current axis position as a reference (the actual motor position stays the same)

**set\_switch\_polarity**(*polarity=False*, *axis=0*, *addr=0*)

Set end switch polarity (*False* for normal, *True* for reversed).

Note that for 3-axis controller (TMCM-3110) the polarity is the same for all axes, and for 6-axis controller (TMCM-6110) it has to be the same for the first 3 and the last 3 axes

**setup\_current**(*drive\_current=None*, *standby\_current=None*, *max\_current=1.0*, *axis=0*, *addr=0*)

Set drive and standby currents.

WARNING: too high of a setting might damage the motor. *drive\_current* is the maximal drive current, which is given as a fraction of the *max\_current* (which is either 1A or 2.8A depending on the hardware jumper, as described in the hardware manual). *standby\_current* is given as a fraction of *drive\_current*. Any *None* parameters are left unchanged.

**setup\_home**(*home\_mode=None*, *search\_speed=None*, *switch\_speed=None*, *axis=0*, *addr=0*)

Setup homing parameters (*mode*, *search\_speed*, *switch\_speed*).

*mode* is one of 16 different values, which can start with "lim\_" indicating reliance on limit switches, or with "home\_" indicating usage of home switches. Home-based switches can also be inverted (with "\_inv" in the end), indicating that the homing switch function is inverted (0 instead of 1 means that the switch is engaged). More details can be found in the manual. *search\_speed* and *switch\_speed* describe, respectively, the initial speed while searching for the switch, and the final homing speed while searching for the edge of the switch action. Both are given in *internal* units.

**setup\_limit\_switches**(*left\_enable=None*, *right\_enable=None*, *axis=0*, *addr=0*)

Setup limit switch parameters

**setup\_velocity**(*speed=None*, *accel=None*, *pulse\_divisor=None*, *ramp\_divisor=None*, *axis=0*, *addr=0*)

Setup velocity parameters (*speed*, *accel*, *pulse\_divisor*, *ramp\_divisor*).

*speed* and *accel* denote, correspondingly, maximal (i.e., steady regime) moving speed and acceleration in *internal* units. *pulse\_divisor* is the driver pulse divisor, which defines how internal velocity units translate into microsteps/s (see [get\\_velocity\\_factor\(\)](#)); rounded to the nearest power of 2, higher values

mean slower motion. `ramp_divisor` is the driver ramp divisor, which, together with the pulse divisor, defines how internal acceleration units translate into microsteps/s<sup>2</sup> (see [`get\_acceleration\_factor\(\)`](#)); rounded to the nearest power of 2, higher values mean slower acceleration. `None` values are left unchanged.

**stop**(*axis=0, addr=0*)

Stop motion

**store\_axis\_parameter**(*parameter, value=None, axis=0, addr=0*)

Store a given axis parameter in EEPROM at the given axis and device address (by default, value is the current value)

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**wait\_move**(*axis=0, addr=0*)

Wait until motion is done

## Module contents

### pylablib.devices.Voltcraft package

#### Submodules

#### pylablib.devices.Voltcraft.base module

**exception** `pylablib.devices.Voltcraft.base.GenericVoltcraftError`

Bases: [`DeviceError`](#)

Generic Voltcraft error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**exception** `pylablib.devices.Voltcraft.base.GenericVoltcraftBackendError`(*exc*)

Bases: [`GenericVoltcraftError`](#), [`DeviceBackendError`](#)

Voltcraft backend communication error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.



**pylablib.devices.Voltcraft.multimeter module**

**class** `pylablib.devices.Voltcraft.multimeter.VC7055(addr)`

Bases: *SCPIDevice*

Voltcraft VC-7055BT bench-top multimeter.

**Parameters**

**addr** – device connection (usually a COM-port name such as "COM1").

**Error**

alias of *GenericVoltcraftError*

**ReraiseError**

alias of *GenericVoltcraftBackendError*

**get\_function**(*channel='primary'*)

Get measurement function for the given measurement channel ("primary" or "secondary", or "all" for both channels)

**set\_function**(*function, channel='primary', reset\_secondary=True*)

Set measurement function for the given measurement channel ("primary", "secondary", or "all" for both channels).

If `reset_secondary==True` and the primary function is changed, set the secondary function to "none" to avoid conflicts.

**get\_range**()

Get the present measurement range

**set\_range**(*rng*)

Set the present measurement range

**is\_autorange\_enabled**()

Check if autoscaling is enabled

**enable\_autorange**(*enable=True*)

Enable or disable autoscaling

**get\_measurement\_rate**()

Get measurement update rate ("fast", "med", or "slow")

**set\_measurement\_rate**(*rate*)

Set measurement update rate ("fast", "med", or "slow")

**get\_reading**(*channel='primary'*)

Return the latest reading of the given measurement channel ("primary", "secondary", or "all" for both channels)

**BackendError**

alias of *DeviceBackendError*

**apply\_settings**(*settings*)

Apply the settings.

*settings* is a dict {name: value} of the available device settings. Non-applicable settings are ignored.

**ask**(*msg*, *data\_type*='string', *delay*=0.0, *timeout*=None, *read\_echo*=False)

Write a message and read a reply.

*msg* is the query message, *delay* is the delay between write and read. Other parameters are the same as in [read\(\)](#). If *read\_echo*==True, assume that the device first echoes the input and skip it.

**close**()

Close the backend

**flush**(*one\_line*=False)

Flush the read buffer (read all the available data and return the number of bytes read).

If *one\_line*==True, read only a single line.

**static get\_arg\_type**(*arg*)

Autodetect argument type

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_esr**(*timeout*=None)

Get the device status register (by default, "\*ESR?" command)

**get\_full\_info**(*include*=0)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_full\_status**(*include*=0)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**get\_id**(*timeout*=None)

Get the device IDN. (query SCPI '\*IDN?' command)

**get\_settings**(*include*=0)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include*=-10 queries all available variables, which is equivalent to *include*="all".

**is\_opened**()

Check if the device is connected

**lock**(*timeout*=None)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout*=None)

Context manager for lock & unlock

**open**()

Open the backend

**static parse\_array\_data**(*data*, *fmt*, *include\_header=False*)

Parse the data returned by the device. *fmt* is [DataFormat](#) description in numpy format (e.g., "<u2").

If *include\_header==True*, the data is assumed to be in a (somewhat) standard SCPI format: `b'#'`, then a single digit *s* denoting length of the size block, then *s* digits denoting length of the data (in bytes) followed by the actual data. Otherwise (*include\_header==False*), assume that the header is already removed.

**read**(*data\_type='string'*, *timeout=None*)

Read data from the device.

*data\_type* determines the type of the data. Can be 'raw' (just raw data), 'string' (with trailing and leading spaces stripped), 'int', 'float', 'bool' (interprets 0 or 'off' as False, anything else as True), 'value' (returns tuple (value, unit), where *value* is float), a callable (return the result of this callable applied to the string value), a dictionary (return the stored value corresponding to the string value, or to the value converted into integer if the string value is not present), or a list of data types (the result is treated as a list of values with the given types separated by commas). *timeout* overrides the default value.

**read\_binary\_array\_data**(*include\_header=False*, *timeout=None*, *flush\_term=True*)

Read a binary data in the from the device.

The data assumes the standard binary transfer header consisting of "#" symbol, then a single digit with the size of the length string, then the length string containing the length of the binary data (in bytes). If *include\_header==True*, return the data with the header; otherwise, return only the content. If *flush\_term==True*, flush the following line to skip terminator characters after the binary data, which are added by some devices. *timeout* overrides the default value.

**reconnect**(*new\_instrument=True*, *ignore\_error=True*)

Remake the connection.

If *new\_instrument==True*, create a new backend instance. If *ignore\_error==True*, ignore errors on closing.

**reset**()

Reset the device (by default, "\*RST" command)

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

**sleep**(*delay*)

Wait for *delay* seconds

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

**using\_write\_buffer**()

Context manager for using a write buffer.

While it's active, all the consecutive [write\(\)](#) operations are bundled together with ; delimiter. The actual write is performed at the [read\(\)/ask\(\)](#) operation or at the end of the block.

**wait**(*wait\_type='sync'*, *timeout=None*, *wait\_callback=None*)

Pause execution until device overlapped commands are complete.

*wait\_type* is either 'sync' (perform [wait\\_sync\(\)](#)), 'dev' (perform [wait\\_dev\(\)](#)) or 'none' (do nothing).

**wait\_dev()**

Pause execution of the device commands until device overlapped commands (e.g., taking sweeps) are complete.

Note that the code execution is not paused.

**wait\_sync**(*timeout=None, wait\_callback=None*)

Pause execution of the script until device overlapped commands (e.g., taking sweeps) are complete.

*timeout* and *wait\_callback* override default constructor parameters.

**write**(*msg, arg=None, arg\_type=None, unit=None, bool\_selector=None, wait\_sync=None, read\_echo=False, read\_echo\_delay=0.0*)

Send a command.

**Parameters**

- **msg** (*str*) – Text message.
- **arg** – Optional argument to append in the end. If a list of arguments is supplied, the result is joined with ", ".
- **arg\_type** (*str*) – Argument type. Can be 'raw' (in which case data is sent raw), 'string', 'int', 'float', 'bool', a format string (such as '{:.3f}') or a list of argument types (for an iterable argument); if format string is used and the argument is a list or a tuple, then it is expanded as a list of arguments (e.g., *arg\_type*='{0};{1}' with *arg*=[1,2] will produce a string '1;2'); if a list of types is used, each element of *arg* is converted using the corresponding type, and the result is joined with ", ".
- **unit** (*str*) – If not None, use it as a unit to append after the value.
- **bool\_selector** (*tuple*) – A tuple (*false\_value*, *true\_value*) of two strings to represent bool argument; by default, use *.\_bool\_selector* attribute.
- **wait\_sync** – if True, append the sync command (specified as *.\_wait\_sync\_comm* attribute, "\*OPC?" by default) after the message and pause the execution command is complete; useful in long set operations, where the device might ignore later inputs until the current command is complete; if None, use the class default *.\_default\_write\_sync* attribute (False by default).
- **read\_echo** (*bool*) – If True, read a single line after write.
- **read\_echo\_delay** (*float*) – The delay between write and read if *read\_echo*==True.

**exception** `pylablib.devices.Voltcraft.multimeter.VC880ParseError`

Bases: *GenericVoltcraftError*

Voltcraft VC880 message parse error

**add\_note()**

`Exception.add_note(note)` – add a note to the exception

**args****with\_traceback()**

`Exception.with_traceback(tb)` – set `self.__traceback__` to `tb` and return `self`.

**class** `pylablib.devices.Voltcraft.multimeter.TVC880Reading`(*func, kind, value, unit, disps, d2func*)

Bases: *tuple*

**d2func****disps****func****kind****unit****value****class** `pylablib.devices.Voltcraft.multimeter.VC880(conn=0)`Bases: [\*ICommBackendWrapper\*](#)

Voltcraft VC880/VC650BT series multimeter.

**Parameters****conn** – device connection (usually, either a HID path, or an integer 0-based index indicating the devices among the ones connected)**Error**alias of [\*GenericVoltcraftError\*](#)**class** `TMessage(typ, payload)`Bases: `tuple`**payload****typ****read\_message(tries=10)**

Read the oldest message in the queue

**exhaust\_messages(nmax=100000, tries=10)**

Read all messages in the queue and return them

*nmax* specifies the maximal number of messages to read (None means reading until available).**send\_message(comm, data=b'', pre\_exhaust=True, reps=1, post\_read=0)**

Send a message containing the given command and data.

If *pre\_exhaust*==True, empty the read queue before sending the message (improves chances of delivery). *reps* specifies the number of exhaust/send cycle repetitions (improves chances of delivery). If *post\_read* is more than 0, it specifies the number of messages to read after the command is sent.**get\_reading(kind='latest')**

Get the multimeter reading.

*kind* can be "latest" (return the most recent reading), "oldest" (return the oldest reading), or "all" (return all readings in the read queue). Return tuple (*func*, *kind*, *val*, *unit*, *disps*, *d2func*) with, correspondingly, specific selected function (e.g., "DCuA" or "res"), function kind (e.g., "curr\_dc" or "res"), displayed value (in SI units), value units (e.g., "V" or "Ohm"), values of the other 3 auxiliary displays (upper right min/max/avg/rel display, upper left memory display, bottom linear scale display), and the kind of function on the upper right display ("min", "max", "avg", or "rel").**enable\_autorange(enable=True)**

Enable or disable autorange

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the backend

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**lock**(*timeout=None*)

Lock the access to the device from other threads/processes (isn't necessarily implemented)

**locking**(*timeout=None*)

Context manager for lock & unlock

**open**()

Open the backend

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**unlock**()

Unlock the access to the device from other threads/processes (isn't necessarily implemented)

## Module contents

### pylablib.devices.Windows package

## Submodules

### pylablib.devices.Windows.joystick module

**class** pylablib.devices.Windows.joystick.**TDeviceInfo**(*name, id, nbuttons, naxes*)

Bases: [tuple](#)

**id**

**name**

**naxes**

**nbuttons**

pylablib.devices.Windows.joystick.**list\_joysticks**()

List all detected joysticks

**class** pylablib.devices.Windows.joystick.**TJoystickEvent**(*kind, index, old, new, timestamp*)

Bases: [tuple](#)

**index**

**kind**

**new**

**old**

**timestamp**

**class** pylablib.devices.Windows.joystick.**TJoystickEventEx**(*kind, index, old, new, state, timestamp*)

Bases: [tuple](#)

**index**

**kind**

**new**

**old**

**state**

**timestamp**

**class** pylablib.devices.Windows.joystick.**Joystick**(*idx=None, expanded\_events=False*)

Bases: [IDevice](#)

Generic Windows joystick device.

#### Parameters

- **idx** – joystick index (0-based) in the list returned by [list\\_joysticks\(\)](#); if None, use the first valid index.

- **expanded\_events** (*bool*) – if True, the events include the full joystick state; otherwise, they only record the change of the state at the particular event

**Error** = <Mock name='mock.WinMMError' id='140527500453712'>

**open()**

Open the connection

**close()**

Close the connection

**is\_opened()**

Check if the device is connected

**start()**

Start the polling loop (used for events recording)

**stop()**

Stop the polling loop

**get\_device\_info()**

Get joystick info.

Return tuple (name, id, nbuttons, naxes).

**get\_buttons()**

Get the buttons state as a list

**get\_axes()**

Get the axes state as a list

**get\_events**(*n=None, clear=True*)

Get recent joystick events.

Note that in order to capture events, one needs to call the **start** method first to start the event loop. *n* specifies the number of oldest uncleared events to get (by default, all events). If **clear==True**, remove all returned events from the queue.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.

**get\_full\_status**(*include=0*)

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting **include=-10** queries all available variables, which is equivalent to **include="all"**.



**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

## Module contents

### pylablib.devices.interface package

#### Submodules

#### pylablib.devices.interface.camera module

**exception** pylablib.devices.interface.camera.DefaultFrameTransferError

Bases: *DeviceError*

Generic frame transfer error

**add\_note**()

Exception.add\_note(note) – add a note to the exception

**args**

**with\_traceback**()

Exception.with\_traceback(tb) – set self.\_\_traceback\_\_ to tb and return self.

**class** pylablib.devices.interface.camera.TFramesStatus(*acquired, unread, skipped, buffer\_size*)

Bases: *tuple*

**acquired**

**buffer\_size**

**skipped**

**unread**

**class** pylablib.devices.interface.camera.TFrameSize(*width, height*)

Bases: *tuple*

**height**

**width**

**class** pylablib.devices.interface.camera.TFramePosition(*left, top*)

Bases: *tuple*

**left**

**top**

**class** pylablib.devices.interface.camera.**TFrameInfo**(*frame\_index*)

Bases: [tuple](#)

**frame\_index**

**class** pylablib.devices.interface.camera.**ICamera**(\*args, \*\*kwargs)

Bases: [IDevice](#)

Generic camera class.

Provides a consistent common interface for the most frequently encountered camera functions.

**Error**

alias of [DeviceError](#)

**TimeoutError**

alias of [DeviceError](#)

**FrameTransferError**

alias of [DefaultFrameTransferError](#)

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**setup\_acquisition**(\*\*kwargs)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition**(\*args, \*\*kwargs)

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of `with` block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`,

stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (None means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (None means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

#### **get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (`width`, `height`)

#### **get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

#### **wait\_for\_frame(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)**

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (`timeout`, `frame_timeout`), in which case the call times out if the total time exceeds `timeout`, or a single frame wait exceeds `frame_timeout`. If the call times out, raise `TimeoutError`. If `error_on_stopped==True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

#### **get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

#### **set\_image\_indexing(*indexing*)**

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

#### **get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (`width`, `height`); take indexing mode into account

#### **get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

#### **set\_frame\_format(*fmt*)**

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the

frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

#### **get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

#### **set\_frame\_info\_format(fmt, include\_fields=None)**

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes) If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

#### **get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

#### **set\_frame\_info\_period(period=1)**

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

#### **get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

#### **get\_new\_images\_range()**

Get the range of the new images.

Return tuple (*first*, *last*) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

#### **read\_multiple\_images(rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False)**

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek*==True, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==True, return tuple (*frames*, *infos*), where *infos* is a

list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied `rng` if some frames are skipped.

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if `None`, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be `"none"` (replacing them with `None`), `"zero"` (replacing them with zero-filled frame), or `"skip"` (skipping them, while still keeping total returned frames number to *n*). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`.

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {`name`: `value`} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or `"all"` (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status**(*include=0*)

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or `"all"` (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_settings**(*include=0*)

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

`pylablib.devices.interface.camera.acqstopped(*args, **kwargs)`

Decorator which temporarily stops acquisition for the function call

`pylablib.devices.interface.camera.acqcleared(*args, **kwargs)`

Decorator which temporarily clears acquisition for the function call

`pylablib.devices.interface.camera.trim_frames(frames, l, info=None, chunks='auto')`

Trim frames in different formats to the desired length

**class** `pylablib.devices.interface.camera.FrameCounter`

Bases: `object`

Frame counter.

Keeps track of the buffer occupation, acquired/missed frames, last read and wait buffers, etc.

**reset**(*buffer\_size=None*)

Reset the counters.

If *buffer\_size* is `None`, assume the the buffer is deallocated. Otherwise, it specifies the frame buffer size (in frames).

**update\_acquired\_frames**(*acquired\_frames*)

Update the counter of acquired frames (needs to be called by the camera whenever necessary)

**wait\_start**(*acquired\_frames*)

Set up waiting routine (called in the beginning of `ICamera.wait_for_frame()`)

**is\_wait\_done**(*acquired\_frames=None, since='lastread', nframes=1*)

Check if the waiting condition is satisfied based on the counter values:

If not `None`, *acquired\_frames* specifies the most recent number of acquired frames (the internal counters is automatically updated). *since* and *nframes* have the same meaning as in `ICamera.wait_for_frame()`.

**wait\_done**()

Clean up waiting routine (called in the end of `ICamera.wait_for_frame()`)

**get\_frames\_status**(*acquired\_frames=None*)

Get status of the internal counters.

Return tuple (acquired, unread, skipped, *buffer\_size*). If the buffer is not allocated, all counters are 0.

**get\_new\_frames\_range**(*acquired\_frames=None*)

Get the range of the new frames (acquired but not read)

**trim\_frames\_range**(*rng*)

Trim the given frames range to only contains frames which are still in the buffer (i.e., remove the frames which are too old and have been overwritten)

**advance\_read\_frames**(*rng*)

Mark the specified frames range as read and advance the last read counter

**set\_first\_valid\_frame**(*first\_valid\_frame*)

Set the first valid frame; all frames older than it are considered invalid when calculating skipped frames and trimming ranges

**class** `pylablib.devices.interface.camera.FrameNotifier`(*strict=False*)

Bases: `object`

Notifier for a new available frame.

Used when the camera runs a separate polling thread or a callback, which needs to notify the main thread that a new frame has been acquired.

#### Parameters

**strict** – determines whether `wait()` waits for a specified frame index, or just for any new frame (which is checked later)

**reset()**

Reset the internal frame counter

**inc()**

Increment the internal frame counter, notify the waiting threads, and return the counter value

**wait**(*idx=None, timeout=None*)

Wait for a new frame with a given index (if `None`, for the next acquired frame)

**class** `pylablib.devices.interface.camera.ChunkBufferManager`(*chunk\_size=67108864*)

Bases: `object`

Buffer manager, which takes care of creating and removing the buffer chunks, and reading out some parts of them.

#### Parameters

**chunk\_size** – the minimal size of a single buffer chunk (continuous memory segment potentially containing several frames).

**get\_ctypes\_frames\_list**(*ctype=<class 'ctypes.c\_char\_p'>*)

Get stored buffers as a ctypes array with pointer of the given type

**get\_frames\_data**(*idx, nframes=1*)

Get frames data starting from *idx* and spanning *nframes* frames.

Return a list of tuples (*nread*, *chunk\_data*), where *nread* is the number of frames in the chunk, and *chunk\_data* is the raw buffer pointer as a `ctypes.c_char_p` object.

**allocate**(*nframes, frame\_size*)

Allocate buffers for the given number of frames and frame size (in bytes)

**deallocate**()

Deallocate the buffers

**class** pylablib.devices.interface.camera.IAttributeCamera(\*args, \*\*kwargs)

Bases: [ICamera](#)

Camera class which supports camera attributes.

The method `_list_attributes` must be defined in a subclass; it should produce a list of camera attributes, which have `name` attribute for placing them into a dictionary. Attributes can also have `readable` and `writable` attributes, which are used in [get\\_all\\_attribute\\_values\(\)](#) and [set\\_all\\_attribute\\_values\(\)](#) to determine if the attribute values should be collected or set. Method `_update_attributes` should be called on opening to populate the dictionary of available attributes.

One can also define `_normalize_attribute_name`, which normalizes the attribute name into a dictionary name (e.g., replaces separators, removes spaces, or normalizes case).

**get\_attribute**(name, error\_on\_missing=True)

Get the camera attribute with the given name

**get\_all\_attributes**(copy=False)

Return a dictionary of all available attributes.

If `copy==True`, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_attribute\_value**(name, error\_on\_missing=True, default=None, \*\*kwargs)

Get value of an attribute with the given name.

If the value doesn't exist and `error_on_missing==True`, raise error; otherwise, return *default*. If *default* is not `None`, automatically assume that `error_on_missing==False`. If *name* points at a dictionary branch, return a dictionary with all values in this branch. Additional arguments are passed to `get_value` methods of the individual attribute.

**set\_attribute\_value**(name, value, error\_on\_missing=True, \*\*kwargs)

Set value of an attribute with the given name.

If the value doesn't exist and `error_on_missing==True`, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). Additional arguments are passed to `set_value` methods of the individual attribute.

**get\_all\_attribute\_values**(root="", \*\*kwargs)

Get values of all attributes with the given *root*.

Additional arguments are passed to `get_value` methods of individual attributes.

**set\_all\_attribute\_values**(settings, root="", \*\*kwargs)

Set values of all attributes with the given *root*.

Additional arguments are passed to `set_value` methods of individual attributes.

#### Error

alias of [DeviceError](#)

#### FrameTransferError

alias of [DefaultFrameTransferError](#)

#### TimeoutError

alias of [DeviceError](#)

**acquisition\_in\_progress**()

Check if acquisition is in progress



**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**close()**

Close the connection

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If `clear==True`, clear acquisition in addition to stopping (by default, use the class default specified as `_clear_pausing_acquisition` attribute). If `stop==True`, stop the acquisition (if `clear==True`, stop regardless). If `setup_after==True`, setup the acquisition after pause if necessary (`None` means setup only if clearing was required). If `start_after==True`, start the acquisition after pause if necessary (`None` means start only if stopping was required). If `combine_nested==True`, then any nested `pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (`first`, `last`) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be `"none"` (replacing them with `None`), `"zero"` (replacing them with zero-filled frame), or `"skip"` (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if `missing_frame=="skip"`, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be `"list"` (list of 2D arrays), `"array"` (a single 3D array), `"chunks"` (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or `"try_chunks"` (same as `"chunks"`, but if chunks are not supported, set to `"list"` instead). If format is `"chunks"` and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to `"array"` or `"chunks"`, the frame info format is also automatically set to `"array"`. If the format is set to `"chunks"`, then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be `"namedtuple"` (potentially nested named tuples; convenient to get particular values), `"list"` (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table),

"array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes) If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition**(\*\**kwargs*)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap**(*timeout=5.0*, *return\_info=False*)

Snap a single frame

**start\_acquisition**(\**args*, \*\**kwargs*)

Start acquisition.

Can take the same keyword parameters as :meth: ``setup\_acquisition``. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread'*, *nframes=1*, *timeout=20.0*, *error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful [wait\\_for\\_frame\(\)](#) call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.interface.camera.IGrabberAttributeCamera`(\**args*, \*\**kwargs*)

Bases: [ICamera](#)

Camera class which supports frame grabber attributes.

Essentially the same as [IAttributeCamera](#), but with relevant methods and attributes renamed to support both frame grabber and camera attributes handling simultaneously.

The method `_list_grabber_attributes` must be defined in a subclass; it should produce a list of camera attributes, which have name attribute for placing them into a dictionary. Attributes can also have readable and writable attributes, which are used in `get_all_grabber_attribute_values()` and `set_all_grabber_attribute_values()` to determine if the attribute values should be collected or set. Method `_update_grabber_attributes` should be called on opening to populate the dictionary of available attributes.

One can also define `_normalize_grabber_attribute_name`, which normalizes the attribute name into a dictionary name (e.g., replaces separators, removes spaces, or normalizes case).

**get\_grabber\_attribute**(*name*, *error\_on\_missing=True*)

Get the camera attribute with the given name

**get\_all\_grabber\_attributes**(*copy=False*)

Return a dictionary of all available frame grabber grabber\_attributes.

If *copy==True*, copy the dictionary; otherwise, return the internal dictionary structure (should not be modified).

**get\_grabber\_attribute\_value**(*name*, *error\_on\_missing=True*, *default=None*, *\*\*kwargs*)

Get value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, return *default*. If *default* is not None, automatically assume that *error\_on\_missing==False*. If *name* points at a dictionary branch, return a dictionary with all values in this branch. Additional arguments are passed to `get_value` methods of the individual attribute.

**set\_grabber\_attribute\_value**(*name*, *value*, *error\_on\_missing=True*, *\*\*kwargs*)

Set value of a frame grabber attribute with the given name.

If the value doesn't exist and *error\_on\_missing==True*, raise error; otherwise, do nothing. If *name* points at a dictionary branch, set all values in this branch (in this case *value* must be a dictionary). Additional arguments are passed to `set_value` methods of the individual attribute.

**get\_all\_grabber\_attribute\_values**(*root=""*, *\*\*kwargs*)

Get values of all frame grabber attributes with the given *root*.

Additional arguments are passed to `get_value` methods of individual attributes.

**set\_all\_grabber\_attribute\_values**(*settings*, *root=""*, *\*\*kwargs*)

Set values of all frame grabber attributes with the given *root*.

Additional arguments are passed to `set_value` methods of individual attributes.

## Error

alias of [\*DeviceError\*](#)

## FrameTransferError

alias of [\*DefaultFrameTransferError\*](#)

## TimeoutError

alias of [\*DeviceError\*](#)

## acquisition\_in\_progress()

Check if acquisition is in progress

## apply\_settings(settings)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**close()**

Close the connection

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested

`pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**`read_multiple_images`**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (`first`, `last`) with images range (`first` inclusive). If no new frames are available, return an empty list; if no acquisition is running, return `None`. If `peek==True`, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is `None`. if `return_rng==True`, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped.

**`read_newest_image`**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**`read_oldest_image`**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**`set_device_variable`**(*key, value*)

Set the value of a settings parameter

**`set_frame_format`**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**`set_frame_info_format`**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes) If *include\_fields* is not `None`, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.



**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition**(\*\**kwargs*)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap**(*timeout=5.0*, *return\_info=False*)

Snap a single frame

**start\_acquisition**(\**args*, \*\**kwargs*)

Start acquisition.

Can take the same keyword parameters as :meth: `setup_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is `None`). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread'*, *nframes=1*, *timeout=20.0*, *error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, `None` (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==`True` and the acquisition is not running, raise `Error`; otherwise, simply return `False` without waiting.

**class** `pylablib.devices.interface.camera.TAcqTimings`(*exposure*, *frame\_period*)

Bases: `tuple`

**exposure**

**frame\_period**

**class** `pylablib.devices.interface.camera.IExposureCamera`(\**args*, \*\**kwargs*)

Bases: `ICamera`

**get\_exposure**()

Get current exposure

**set\_exposure**(*exposure*)

Set camera exposure

**get\_frame\_period**()

Get frame period (time between two consecutive frames in the internal trigger mode)

**get\_frame\_timings**()

Get acquisition timing.

Return tuple (exposure, frame\_period).

**Error**

alias of *DeviceError*

**FrameTransferError**

alias of *DefaultFrameTransferError*

**TimeoutError**

alias of *DeviceError*

**acquisition\_in\_progress**()

Check if acquisition is in progress

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition**()

Clear acquisition settings

**close**()

Close the connection

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size**()

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields**()

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab**(*nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None*)

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if *None*, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*.

**is\_acquisition\_setup**()

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return *True*.

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of *with* block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (*None* means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (*None* means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress*, *acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (*first* inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (frame, info), where info is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fnt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fnt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not None, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition**(*\*\*kwargs*)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**start\_acquisition**(*\*args, \*\*kwargs*)

Start acquisition.

Can take the same keyword parameters as *meth: `setup\_acquisition`*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is None).

Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.interface.camera.TAxisROILimit`(*min, max, pstep, sstep, maxbin*)

Bases: `tuple`

**max**

**maxbin**

**min**

**pstep**

**sstep**

`pylablib.devices.interface.camera.truncate_roi_axis`(*roi, lim, symmetric=False*)

Truncate ROI to conform to the given ROI limits.

*roi* is a tuple (start, stop, bin), and *lim* is a tuple (min, max, pstep, sstep, maxbin). Assume that pstep and sstep divide min and max, and that either pstep divides sstep or the other way around. If *symmetric*==True, then max should be even.

**class** `pylablib.devices.interface.camera.IROICamera`(\*args, \*\*kwargs)

Bases: `ICamera`

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0).

**set\_roi**(*hstart=0, hend=None, vstart=0, vend=None*)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0). By default, all non-supplied parameters take extreme values (0 for start, maximal for end).

**get\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (min, max, pstep, sstep, maxbin) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning (fixed to 1 if not binning is allowed). In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**Error**

alias of *DeviceError*

**FrameTransferError**

alias of *DefaultFrameTransferError*

**TimeoutError**

alias of *DeviceError*

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings(settings)**

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**close()**

Close the connection

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {name: value}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by *set\_frame\_info\_format()*) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by *get\_frame\_info\_fields()*; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (`acquired`, `unread`, `skipped`, `size`), where `acquired` is the total number of acquired frames, `unread` is the number of acquired but not read frames, `skipped` is the number of skipped (not read and then written over) frames, and `buffer_size` is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {`name`: `value`} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_full\_status(include=0)**

Get dict {`name`: `value`} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (`first`, `last`) with images range (first inclusive). If no images are available, return `None`. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {`name`: `value`} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting `include=-10` queries all available variables, which is equivalent to `include="all"`.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if `None`, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with `None`), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If `return_info==True`, return tuple (`frames`, `infos`), where `infos` is a list of frame info tuples (camera-dependent); if some frames are missing and `missing_frame!="skip"`, the corresponding frame info is `None`.



**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**pausing\_acquisition**(*clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True*)

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (*acq\_in\_progress, acq\_params*), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first, last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames, infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame, info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return None. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame, info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format(*fmt*)**

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format(*fmt*, *include\_fields=None*)**

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period(*period=1*)**

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing(*indexing*)**

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition(\*\**kwargs*)**

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap(*timeout=5.0*, *return\_info=False*)**

Snap a single frame

**start\_acquisition(\**args*, \*\**kwargs*)**

Start acquisition.

Can take the same keyword parameters as *meth: ``setup\_acquisition``*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [setup\\_acquisition\(\)](#), if the parameter is *None*). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**wait\_for\_frame(*since='lastread'*, *nframes=1*, *timeout=20.0*, *error\_on\_stopped=False*)**

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**class** `pylablib.devices.interface.camera.IBinROICamera(*args, **kwargs)`

Bases: `ICamera`

**get\_roi()**

Get current ROI.

Return tuple (*hstart*, *hend*, *vstart*, *vend*, *hbin*, *vbin*). *hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning.

**set\_roi**(*hstart*=0, *hend*=None, *vstart*=0, *vend*=None, *hbin*=1, *vbin*=1)

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start is inclusive, stop is exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values (0 for start, maximal for end, 1 for binning).

**get\_roi\_limits**(*hbin*=1, *vbin*=1)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim*, *vlim*), where each element is in turn a limit 5-tuple (*min*, *max*, *pstep*, *sstep*, *maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**Error**

alias of `DeviceError`

**FrameTransferError**

alias of `DefaultFrameTransferError`

**TimeoutError**

alias of `DeviceError`

**acquisition\_in\_progress()**

Check if acquisition is in progress

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**clear\_acquisition()**

Clear acquisition settings

**close()**

Close the connection

**get\_acquisition\_parameters()**

Get acquisition parameters.

Return dictionary {*name*: *value*}

**get\_data\_dimensions()**

Get readout data dimensions (in pixels) as a tuple (width, height); take indexing mode into account

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_frame\_format()**

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields()**

Get the names of frame info fields.

Applicable when frame info format (set by `set_frame_info_format()`) is "list" or "array".

**get\_frame\_info\_format()**

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by `get_frame_info_fields()`; convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period()**

Get period of frame info acquisition.

Frame info might be skipped (set to None) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where *acquired* is the total number of acquired frames, *unread* is the number of acquired but not read frames, *skipped* is the number of skipped (not read and then written over) frames, and *buffer\_size* is the total buffer size (in frames).

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested *pausing\_acquisition* calls will stop/clear acquisition as necessary, but won't setup/start it again until this *pausing\_acquisition* call is complete.

Yields tuple (acq\_in\_progress, acq\_params), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return *None*. If *peek==True*, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with *None*), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info==True*, return tuple (*frames*, *infos*), where *infos* is a list of frame info tuples (camera-dependent, by default, only the frame index); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is *None*. if *return\_rng==True*, return the range covered resulting frames; if *missing\_frame=="skip"*, the range can be smaller than the supplied *rng* if some frames are skipped.

**read\_newest\_image**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**read\_oldest\_image**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return *None*. If *peek==True*, return the image but not mark it as read. If *return\_info==True*, return tuple (*frame*, *info*), where *info* is an info tuples (camera-dependent, see [read\\_multiple\\_images\(\)](#)).

**set\_device\_variable**(*key, value*)

Set the value of a settings parameter

**set\_frame\_format**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**set\_frame\_info\_format**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If *include\_fields* is not *None*, it specifies the fields included for non-"tuple" formats; note that order or *include\_fields* is ignored, and the resulting fields are always ordered same as in the original.

**set\_frame\_info\_period**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**set\_image\_indexing**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**setup\_acquisition**(\*\**kwargs*)

Setup acquisition.

Any non-specified acquisition parameters are assumed to be the same as previously set (or default, if not explicitly set before). Return the new acquisition parameters.

**snap**(*timeout=5.0*, *return\_info=False*)

Snap a single frame

**start\_acquisition**(\**args*, \*\**kwargs*)

Start acquisition.

Can take the same keyword parameters as :meth:`setup\_acquisition`. If the acquisition is not set up yet, set it up using the supplied parameters (use default of `setup_acquisition()`, if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition**()

Stop acquisition

**wait\_for\_frame**(*since='lastread'*, *nframes=1*, *timeout=20.0*, *error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

```
class pylablib.devices.interface.camera.TStatusLineDescription(kind, roi, framestamp_checker)
```

Bases: `tuple`

**framestamp\_checker**

**kind**

**roi**

```
class pylablib.devices.interface.camera.StatusLineChecker
```

Bases: `object`

Class responsible for checking status line consistency

**get\_framestamp**(*frames*)

Get framestamps from status lines in the given frames

**check\_indices**(*indices*, *step=1*)

Check if indices are consistent with the given step

```
pylablib.devices.interface.camera.remove_status_line(frame, status_line, policy='duplicate',  
                                                    copy=True, value=0)
```

Remove status line, if present.

#### Parameters

- **frame** – a frame to process (2D or 3D numpy array; if 3D, the first axis is the frame number)
- **status\_line** – status line descriptor (from the frames message)
- **policy** – determines way to deal with the status line; can be "keep" (keep as is), "cut" (cut off the status-line-containing row/column), "zero" (set it to zero), "value" (set it to a given value), "median" (set it to the image median), or "duplicate" (set it equal to the previous row; default) "cut" is only possible if the status line is on the edge of the image.
- **copy** – if True, make copy of the original frames; otherwise, attempt to remove the line in-place

```
pylablib.devices.interface.camera.extract_status_line(frame, status_line, copy=True)
```

Extract status line, if present.

#### Parameters

- **frame** – a frame to process (2D or 3D numpy array; if 3D, the first axis is the frame number)
- **status\_line** – status line descriptor (from the frames message)
- **copy** – if True, make copy of the original status line data.

```
pylablib.devices.interface.camera.insert_status_line(frame, status_line, value, copy=True)
```

Insert status line, if present.

#### Parameters

- **frame** – a frame to process (2D or 3D numpy array; if 3D, the first axis is the frame number)
- **status\_line** – status line descriptor (from the frames message)
- **value** – status line value
- **copy** – if True, make copy of the original status line data.

```
pylablib.devices.interface.camera.get_status_line_roi(frame, status_line)
```

Return ROI taken by the status line in the given frame

## pylablib.devices.interface.stage module

```
class pylablib.devices.interface.stage.IStage
```

Bases: *IDevice*

Generic stage class

```
apply_settings(settings)
```

Apply the settings.

*settings* is the dict {name: value} of the device available settings. Non-applicable settings are ignored.



**close()**

Close the connection

**get\_device\_variable(key)**

Get the value of a settings, status, or full info parameter

**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened()**

Check if the device is connected

**open()**

Open the connection

**set\_device\_variable(key, value)**

Set the value of a settings parameter

`pylablib.devices.interface.stage.muxaxis(*args, argname='axis', **kwargs)`

Multiplex the function over its axis argument

**class** `pylablib.devices.interface.stage.IMultiaxisStage(*args, default_axis='all', **kwargs)`

Bases: *IStage*

Generic multiaxis stage class.

Has methods to assign and map axes and the axis device parameter.

**Parameters**

**default\_axis** – default axis parameter value used when *axis=None* is provided

**get\_all\_axes()**

Get the list of all available axes (taking mapping into account)

**remap\_axes(mapping, accept\_original=True)**

Rename axes to the new labels.

*mapping* is the new axes mapping, which can be a list of new axes name (corresponding to the old axes in order returned by `get_all_axes()`), or a dictionary {alias: original} of the new axes aliases.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name*: *value*} of the device available settings. Non-applicable settings are ignored.

**close**()

Close the connection

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_full\_info**(*include=0*)

Get dict {*name*: *value*} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status**(*include=0*)

Get dict {*name*: *value*} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_settings**(*include=0*)

Get dict {*name*: *value*} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**is\_opened**()

Check if the device is connected

**open**()

Open the connection

**set\_device\_variable**(*key*, *value*)

Set the value of a settings parameter

## Module contents

### pylablib.devices.uc480 package

#### Submodules

#### pylablib.devices.uc480.uc480 module

```
class pylablib.devices.uc480.uc480.TCameraInfo(cam_id, dev_id, sens_id, model, serial_number,  
                                              in_use, status)
```

Bases: `tuple`

`cam_id`

**dev\_id****in\_use****model****sens\_id****serial\_number****status****pylablib.devices.uc480.uc480.list\_cameras**(*backend*='uc480')

List all uc480/uEye camera connections (interface kind and camera index).

*backend* is the camera DLL backend; can be either "uc480" for Thorlabs-associated cameras, or "ueye" for IDS uEye-associated cameras**pylablib.devices.uc480.uc480.get\_cameras\_number**(*backend*='uc480')

Get the total number of connected uc480/uEye cameras.

*backend* is the camera DLL backend; can be either "uc480" for Thorlabs-associated cameras, or "ueye" for IDS uEye-associated cameras**pylablib.devices.uc480.uc480.find\_by\_serial**(*serial\_number*, *backend*='uc480')

Find device ID using its serial number.

*backend* is the camera DLL backend; can be either "uc480" for Thorlabs-associated cameras, or "ueye" for IDS uEye-associated cameras**class** pylablib.devices.uc480.uc480.**TDeviceInfo**(*cam\_id*, *model*, *manufacturer*, *serial\_number*,  
*usb\_version*, *date*, *dll\_version*, *camera\_type*)Bases: `tuple`**cam\_id****camera\_type****date****dll\_version****manufacturer****model****serial\_number****usb\_version****class** pylablib.devices.uc480.uc480.**TAcquiredFramesStatus**(*acquired*, *transfer\_missed*,  
*frameskip\_events*)Bases: `tuple`**acquired****frameskip\_events****transfer\_missed**

```
class pylablib.devices.uc480.uc480.TTimestamp(year, month, day, hour, minute, second, millisecond)
```

Bases: `tuple`

`day`

`hour`

`millisecond`

`minute`

`month`

`second`

`year`

```
class pylablib.devices.uc480.uc480.TFrameInfo(frame_index, framestamp, timestamp, timestamp_dev,  
                                              size, io_status, flags)
```

Bases: `tuple`

`flags`

`frame_index`

`framestamp`

`io_status`

`size`

`timestamp`

`timestamp_dev`

```
class pylablib.devices.uc480.uc480.UC480Camera(cam_id=0, roi_binning_mode='auto', dev_id=None,  
                                              backend='uc480')
```

Bases: `IBinROICamera`, `IExposureCamera`

Thorlabs uc480 / IDS uEye camera.

#### Parameters

- **cam\_id** (*int*) – camera ID; use 0 to get the first available camera
- **roi\_binning\_mode** – determines whether binning in ROI refers to binning or subsampling; can be "bin", "subsample", or "auto" (since most cameras only support one, it will pick the one which has non-trivial value, or "bin" if both are available).
- **dev\_id** (*int*) – if `None` use *cam\_id* as a camera id (*cam\_id* field of the camera info returned by `list_cameras()`); otherwise, ignore value of *cam\_id* and use *dev\_id* as device id (*dev\_id* field of the camera info). The first method requires assigning camera IDs beforehand (otherwise IDs might overlap, in which case only one camera can be accessed), but the assigned IDs are permanent; the second method always has unique IDs, but they might change if the cameras are disconnected and reconnected. For a more reliable assignment, one can use `find_by_serial()` function to find device ID based on the camera serial number.
- **backend** – camera DLL backend; can be either "uc480" for Thorlabs-associated cameras, or "ueye" for IDS uEye-associated cameras

```

Error = <Mock name='mock.uc480Error' id='140527492052880'>

TimeoutError = <Mock spec='str' id='140527492051344'>

FrameTransferError = <Mock spec='str' id='140527492333840'>

static find_by_serial(serial_number, backend='uc480')

open()
    Open connection to the camera

close()
    Close connection to the camera

is_opened()
    Check if the device is connected

get_device_info()
    Get camera model data.

    Return tuple (model, manufacturer, serial_number, usb_version, date, dll_version,
    camera_type).

get_camera_id()
    Get the current camera id

set_camera_id(cam_id)
    Set the new camera id (stored in non-volatile memory, i.e., survives power cycling)

set_trigger_mode(mode)
    Set trigger mode.

    Can be "int" (internal), "ext_rise" (external, rising edge), "ext_fall" (external, falling edge), or
    "software" (software trigger).

get_trigger_mode()
    Get trigger mode.

    Can be "int" (internal), "ext_rise" (external, rising edge), "ext_fall" (external, falling edge), or
    "software" (software trigger).

get_frame_timings()
    Get acquisition timing.

    Return tuple (exposure, frame_period).

set_exposure(exposure)
    Set camera exposure

set_frame_period(frame_time)
    Set frame period (time between two consecutive frames in the internal trigger mode)

get_pixel_rate()
    Get camera pixel rate (in Hz)

get_available_pixel_rates()
    Get all available pixel rates (in Hz)

```

**get\_pixel\_rates\_range()**

Get range of allowed pixel rates (in Hz).

Return tuple (min, max, step) if minimal and maximal value, and a step.

**set\_pixel\_rate(rate=None)**

Set camera pixel rate (in Hz)

The rate is always rounded to the closest available. If *rate* is None, set the maximal possible rate.

**get\_all\_color\_modes()**

Get a list of all available color modes

**get\_color\_mode()**

Get current color mode.

For possible modes, see [\*get\\_all\\_color\\_modes\(\)\*](#).

**set\_color\_mode(mode)**

Set current color mode.

For possible modes, see [\*get\\_all\\_color\\_modes\(\)\*](#).

**get\_gains()**

Get current gains.

Return tuple (master, red, green, blue) of corresponding gain factors.

**get\_max\_gains()**

Get maximal gains.

Return tuple (master, red, green, blue) of corresponding maximal gain factors.

**set\_gains(master=None, red=None, green=None, blue=None)**

Set current gains.

If supplied value is None, keep it unchanged.

**get\_gain\_boost()**

Check if gain boost is enabled

**set\_gain\_boost(enabled)**

Enable or disable gain boost

**setup\_acquisition(nframes=100)**

Setup acquisition.

*nframes* determines number of size of the ring buffer (by default, 100).

**clear\_acquisition()**

Clear acquisition settings

**start\_acquisition(\*args, \*\*kwargs)**

Start acquisition.

Can take the same keyword parameters as *meth: ``setup\_acquisition``*. If the acquisition is not set up yet, set it up using the supplied parameters (use default of [\*setup\\_acquisition\(\)\*](#), if the parameter is None). Otherwise, if any supplied parameters are different from the current ones, change them and reset the acquisition.

**stop\_acquisition()**

Stop acquisition

**acquisition\_in\_progress()**

Check if acquisition is in progress

**get\_frames\_status()**

Get acquisition and buffer status.

Return tuple (acquired, unread, skipped, size), where acquired is the total number of acquired frames, unread is the number of acquired but not read frames, skipped is the number of skipped (not read and then written over) frames, and buffer\_size is the total buffer size (in frames).

**get\_acquired\_frame\_status()****set\_frameskip\_behavior(*behavior*)**

Choose the camera behavior if frame skip event is encountered when waiting for a new frame, reading frames, getting buffer status, etc.

Can be "error" (raise `uc480FrameTransferError`), "ignore" (continue acquisition, ignore the gap), or "skip" (mark some number of frames as skipped, but keep the frame counters consistent).

**get\_supported\_subsampling\_modes()**

Get all supported subsampling modes.

Return tuple (horizontal, vertical) of lists with all possible supported subsampling factors.

**get\_subsampling()**

Get current subsampling

**set\_subsampling(*hsub=1, vsub=1*)**

Set subsampling.

If values are not supported, get the closest value below the requested. Automatically turns off binning.

**get\_supported\_binning\_modes()**

Get all supported binning modes.

Return tuple (horizontal, vertical) of lists with all possible supported binning factors.

**get\_binning()**

Get current binning

**set\_binning(*hbin=1, vbin=1*)**

Set binning.

If values are not supported, get the closest value below the requested. Automatically turns off subsampling.

**get\_detector\_size()**

Get camera detector size (in pixels) as a tuple (width, height)

**get\_roi()**

Get current ROI.

Return tuple (hstart, hend, vstart, vend, hbin, vbin).

**set\_roi(*hstart=0, hend=None, vstart=0, vend=None, hbin=1, vbin=1*)**

Setup camera ROI.

*hstart* and *hend* specify horizontal image extent, *vstart* and *vend* specify vertical image extent (start are inclusive, stop are exclusive, starting from 0), *hbin* and *vbin* specify binning. By default, all non-supplied parameters take extreme values.

**get\_roi\_limits**(*hbin=1, vbin=1*)

Get the minimal and maximal ROI parameters.

Return tuple (*hlim, vlim*), where each element is in turn a limit 5-tuple (*min, max, pstep, sstep, maxbin*) with, correspondingly, minimal and maximal size, position and size step, and the maximal binning. In some cameras, the step and the minimal size depend on the binning, which can be supplied.

**apply\_settings**(*settings*)

Apply the settings.

*settings* is the dict {*name: value*} of the device available settings. Non-applicable settings are ignored.

**get\_acquisition\_parameters**()

Get acquisition parameters.

Return dictionary {*name: value*}

**get\_data\_dimensions**()

Get readout data dimensions (in pixels) as a tuple (*width, height*); take indexing mode into account

**get\_device\_variable**(*key*)

Get the value of a settings, status, or full info parameter

**get\_exposure**()

Get current exposure

**get\_frame\_format**()

Get format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), or "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance).

**get\_frame\_info\_fields**()

Get the names of frame info fields.

Applicable when frame info format (set by [set\\_frame\\_info\\_format\(\)](#)) is "list" or "array".

**get\_frame\_info\_format**()

Get format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [get\\_frame\\_info\\_fields\(\)](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes)

**get\_frame\_info\_period**()

Get period of frame info acquisition.

Frame info might be skipped (set to *None*) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**get\_frame\_period**()

Get frame period (time between two consecutive frames in the internal trigger mode)



**get\_full\_info(include=0)**

Get dict {name: value} containing full device information (including status and settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_full\_status(include=0)**

Get dict {name: value} containing the device status (including settings).

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**get\_image\_indexing()**

Get indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**get\_new\_images\_range()**

Get the range of the new images.

Return tuple (first, last) with images range (first inclusive). If no images are available, return None. If some images were in the buffer were overwritten, exclude them from the range.

**get\_settings(include=0)**

Get dict {name: value} containing all the device settings.

*include* specifies either a list of variables (only these variables are returned), a priority threshold (only values with the priority equal or higher are returned), or "all" (all available variables). Since the lowest priority is -10, setting *include=-10* queries all available variables, which is equivalent to *include="all"*.

**grab(nframes=1, frame\_timeout=5.0, missing\_frame='skip', return\_info=False, buff\_size=None)**

Snap *nframes* images (with preset image read mode parameters)

*buff\_size* determines buffer size (if None, use the default size). Timeout is specified for a single-frame acquisition, not for the whole acquisition time. *missing\_frame* determines what to do with frames which have been lost: can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them, while still keeping total returned frames number to *n*). If *return\_info==True*, return tuple (frames, infos), where *infos* is a list of frame info tuples (camera-dependent); if some frames are missing and *missing\_frame!="skip"*, the corresponding frame info is None.

**is\_acquisition\_setup()**

Check if acquisition is set up.

If the camera does not support separate acquisition setup, always return True.

**pausing\_acquisition(clear=None, stop=True, setup\_after=None, start\_after=True, combine\_nested=True)**

Context manager which temporarily pauses acquisition during execution of with block.

Useful for applying certain settings which can't be changed during the acquisition. If *clear==True*, clear acquisition in addition to stopping (by default, use the class default specified as *\_clear\_pausing\_acquisition* attribute). If *stop==True*, stop the acquisition (if *clear==True*, stop regardless). If *setup\_after==True*, setup the acquisition after pause if necessary (None means setup only if clearing was required). If *start\_after==True*, start the acquisition after pause if necessary (None means start only if stopping was required). If *combine\_nested==True*, then any nested

`pausing_acquisition` calls will stop/clear acquisition as necessary, but won't setup/start it again until this `pausing_acquisition` call is complete.

Yields tuple (`acq_in_progress`, `acq_params`), which indicates whether acquisition is currently in progress, and what are the current acquisition parameters.

**`read_newest_image`**(*peek=False, return\_info=False*)

Read the newest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [`read\_multiple\_images\(\)`](#)).

**`read_oldest_image`**(*peek=False, return\_info=False*)

Read the oldest un-read image.

If no un-read frames are available, return `None`. If `peek==True`, return the image but not mark it as read. If `return_info==True`, return tuple (`frame`, `info`), where `info` is an info tuples (camera-dependent, see [`read\_multiple\_images\(\)`](#)).

**`set_device_variable`**(*key, value*)

Set the value of a settings parameter

**`set_frame_format`**(*fmt*)

Set format for the returned images.

Can be "list" (list of 2D arrays), "array" (a single 3D array), "chunks" (list of 3D "chunk" arrays; supported for some cameras and provides the best performance), or "try\_chunks" (same as "chunks", but if chunks are not supported, set to "list" instead). If format is "chunks" and chunks are not supported by the camera, it results in one frame per chunk. Note that if the format is set to "array" or "chunks", the frame info format is also automatically set to "array". If the format is set to "chunks", then the image info is also returned in chunks form (list of 2D info arrays with the same length as the corresponding frame chunks).

**`set_frame_info_format`**(*fmt, include\_fields=None*)

Set format of the frame info.

Can be "namedtuple" (potentially nested named tuples; convenient to get particular values), "list" (flat list of values, with field names are given by [`get\_frame\_info\_fields\(\)`](#); convenient for building a table), "array" (same as "list", but with a numpy array, which is easier to use for "chunks" frame format), or "dict" (flat dictionary with the same fields as the "list" format; more resilient to future format changes). If `include_fields` is not `None`, it specifies the fields included for non-"tuple" formats; note that order or `include_fields` is ignored, and the resulting fields are always ordered same as in the original.

**`set_frame_info_period`**(*period=1*)

Set period of frame info acquisition.

Frame info might be skipped (set to `None`) except for frames which indices are divisible by *period*. Useful for certain cameras where acquiring frame info takes a lot of time and can reduce performance at higher frame rates. Note that this parameter can still be ignored (i.e., always set to 1) if the performance is not an issue for a given camera class.

**`set_image_indexing`**(*indexing*)

Set up indexing for the returned images.

Can be "rct" (first index row, second index column, rows counted from the top), "rcb" (same as "rc", rows counted from the bottom), "xyt" (first index column, second index row, rows counted from the top), or "xyb" (same as "xyt", rows counted from the bottom)

**snap**(*timeout=5.0, return\_info=False*)

Snap a single frame

**wait\_for\_frame**(*since='lastread', nframes=1, timeout=20.0, error\_on\_stopped=False*)

Wait for one or several new camera frames.

*since* specifies the reference point for waiting to acquire *nframes* frames; can be "lastread" (from the last read frame), "lastwait" (wait for the last successful `wait_for_frame()` call), "now" (from the start of the current call), or "start" (from the acquisition start, i.e., wait until *nframes* frames have been acquired). *timeout* can be either a number, None (infinite timeout), or a tuple (*timeout*, *frame\_timeout*), in which case the call times out if the total time exceeds *timeout*, or a single frame wait exceeds *frame\_timeout*. If the call times out, raise `TimeoutError`. If *error\_on\_stopped*==True and the acquisition is not running, raise `Error`; otherwise, simply return False without waiting.

**read\_multiple\_images**(*rng=None, peek=False, missing\_frame='skip', return\_info=False, return\_rng=False*)

Read multiple images specified by *rng* (by default, all un-read images).

If *rng* is specified, it is a tuple (*first*, *last*) with images range (first inclusive). If no new frames are available, return an empty list; if no acquisition is running, return None. If *peek*==True, return images but not mark them as read. *missing\_frame* determines what to do with frames which are out of range (missing or lost): can be "none" (replacing them with None), "zero" (replacing them with zero-filled frame), or "skip" (skipping them). If *return\_info*==True, return tuple (*frames*, *infos*), where *infos* is a list of `TFrameInfo` instances describing frame index, framestamp, global timestamp (real time), device timestamp (time from camera restart, in 0.1us steps), frame size, digital input state, and additional flags; if some frames are missing and *missing\_frame*!="skip", the corresponding frame info is None. if *return\_rng*==True, return the range covered resulting frames; if *missing\_frame*=="skip", the range can be smaller than the supplied *rng* if some frames are skipped. Note that obtaining frame info might take about 2ms, so at high frame rates it will become a limiting factor.

## Module contents

### pylablib.devices.utils package

#### Submodules

#### pylablib.devices.utils.color module

`pylablib.devices.utils.color.bayer_interpolate`(*src, off=(0, 0)*)

Interpolate Bayer-filtered source image.

The algorithm is the straightforward linear nearest neighbor interpolation. The Bayer pattern is assume to be [RG|GB], and *off* specifies the red pixel position with respect to the image origin.

`pylablib.devices.utils.color.linear_to_sRGB`(*v, base=1, A=2.4, P=0.055*)

Convert the linear sRGB color space to the sRGB.

*base* specifies the full color range (e.g., 65535 for 16-bit color values), and *A* and *P* are the two conversion parameters.

`pylablib.devices.utils.color.sRGB_to_linear`(*v, base=1, A=2.4, P=0.055*)

Convert the sRGB color space to the linear sRGB.

*base* specifies the full color range (e.g., 65535 for 16-bit color values), and *A* and *P* are the two conversion parameters.

## pylablib.devices.utils.load\_lib module

`pylablib.devices.utils.load_lib.get_os_lib_folder()`

Get default Windows DLL folder (System32 or SysWOW64, depending on Python and Windows bitness)

`pylablib.devices.utils.load_lib.get_program_files_folder(subfolder="", arch=None)`

Get default Windows Program Files folder or a subfolder within it.

If *arch* is *None*, use the current Python architecture to determine the folder; otherwise, it specifies the architecture ("32bit" for Program Files (x86), "64bit" for Program Files)

`pylablib.devices.utils.load_lib.get_appdata_folder(subfolder="", kind='roaming')`

Get user AppData folder (used to install software only for specific users).

*kind* can be "roaming" (return Roaming AppData folder) or "local" (return Local AppData folder).

`pylablib.devices.utils.load_lib.get_environ_folder(var, subfolder="", error_missing=False)`

Get subfolder of a folder based on the environment variable.

If the environment variable is missing and *error\_missing*==True, raise an error; otherwise, return *None*.

`pylablib.devices.utils.load_lib.load_lib(name, locations=('global',), call_conv='cdecl', locally=False, depends=None, depends_required=True, error_message=None, check_order='location', return_location=False)`

Load DLL.

### Parameters

- **name** – name or path of the library (can also be a list or a tuple with several names, which are tried in that order).
- **locations** – list or tuple of locations to search for a library; the function tries locations in order and returns the first successfully loaded library a location is a string which can be a path to the containing folder, "parameter/\*" (the remaining part is a subpath inside "devices/dlls" library parameters; if this parameter is defined, it names folder or file for the dll), or "global" (load path as is; also searches in the standard OS specified locations determined by PATH variable, e.g., System32 folder).
- **depends** – if specified, it is a list of dependency libraries which need to be loaded first before the main DLL; they are assumed to be in the same location as the main file
- **depends\_required** – if False, ignore errors during dependency loads
- **locally** (*bool*) – if True, prepend path to the DLL containing folder to the environment PATH folders; this is usually required, if the loaded DLL imports other DLLs in the same folder
- **call\_conv** (*str*) – DLL call convention; can be either "cdecl" (corresponds to `ctypes.cdll`) or "stdcall" (corresponds to `ctypes.windll`)
- **error\_message** (*str*) – error message to add in addition to the default error message shown when the DLL is not found
- **check\_order** (*str*) – determines the order in which possible combinations of names and locations are looped over; can be "location" (loop over locations, and for each location loop over names), "name" (loop over names, and for each name loop over locations), or a list of tuples [(loc, name)] specifying order of checking (in the latter case, *name* and *location* arguments are ignored, except for generating error message).

- **return\_location** (*bool*) – if True, return a tuple (dll, location, folder) instead of a single dll.

**class** pylablib.devices.utils.load\_lib.**TLibraryOpenResult**(*init\_result, open\_result, opid*)

Bases: *tuple*

**init\_result**

**open\_result**

**opid**

**class** pylablib.devices.utils.load\_lib.**TLibraryCloseResult**(*close\_result, uninit\_result*)

Bases: *tuple*

**close\_result**

**uninit\_result**

**class** pylablib.devices.utils.load\_lib.**LibraryController**(*lib*)

Bases: *object*

Simple wrapper to control libraries which require initialization when a new device is opened or shutdown when all devices are closed.

**Parameters**

**lib** – controlled library

**preinit()**

Pre-initialize the library, if it hasn't been done already

**open()**

Mark device opening.

Return tuple (*init\_result, open\_result, opid*) with the results of the initialization and the opening, and the opening ID which should afterwards be used for closing. If library is already initialized, set *init\_result=None*

**close**(*opid*)

Mark device closing.

Return tuple (*close\_result, uninit\_result*) with the results of the closing and the shutdown. If library does not need to be shut down yet, set *uninit\_result=None*

**temp\_open()**

Context for temporarily opening a new device connection

**shutdown()**

Close all opened connections and shutdown the library

**get\_opened\_num()**

Get number of opened devices

## Module contents

## Module contents

## Submodules

### pylablib.widgets module

## Module contents

`pylablib.setbp()`

`pylablib.reload_all(from_load_path=True, keep_parameters=True)`

Reload all loaded modules.

If `keep_parameters==True`, keep the current library parameters (`pylablib.par`); otherwise, reset them to default.

`pylablib.unload_all()`

Reload all loaded modules.

`pylablib.load_par(path)`

Load library parameters from a file

## INDICES AND TABLES

- `genindex`
- `modindex`
- `search`





## PYTHON MODULE INDEX

### p

- `pylablib`, 1034
- `pylablib.core`, 455
  - `pylablib.core.dataproc`, 165
    - `pylablib.core.dataproc.callable`, 129
    - `pylablib.core.dataproc.ctransform_fallback`, 134
    - `pylablib.core.dataproc.feature`, 135
    - `pylablib.core.dataproc.filters`, 137
    - `pylablib.core.dataproc.fitting`, 141
    - `pylablib.core.dataproc.fourier`, 144
    - `pylablib.core.dataproc.iir_transform`, 147
    - `pylablib.core.dataproc.image`, 147
    - `pylablib.core.dataproc.interpolate`, 148
    - `pylablib.core.dataproc.specfunc`, 151
    - `pylablib.core.dataproc.table_wrap`, 152
    - `pylablib.core.dataproc.transform`, 161
    - `pylablib.core.dataproc.utils`, 162
  - `pylablib.core.devio`, 202
    - `pylablib.core.devio.backend_logger`, 169
    - `pylablib.core.devio.base`, 170
    - `pylablib.core.devio.comm_backend`, 170
    - `pylablib.core.devio.data_format`, 193
    - `pylablib.core.devio.hid`, 194
    - `pylablib.core.devio.hid_base`, 196
    - `pylablib.core.devio.interface`, 196
    - `pylablib.core.devio.SCPI`, 165
  - `pylablib.core.fileio`, 232
    - `pylablib.core.fileio.datafile`, 202
    - `pylablib.core.fileio.dict_entry`, 203
    - `pylablib.core.fileio.loadfile`, 210
    - `pylablib.core.fileio.loadfile_utils`, 216
    - `pylablib.core.fileio.location`, 217
    - `pylablib.core.fileio.parse_csv`, 222
    - `pylablib.core.fileio.savefile`, 224
    - `pylablib.core.fileio.table_stream`, 231
  - `pylablib.core.gui`, 330
    - `pylablib.core.gui.formatter`, 306
    - `pylablib.core.gui.limiter`, 308
    - `pylablib.core.gui.utils`, 309
    - `pylablib.core.gui.value_handling`, 311
    - `pylablib.core.gui.widgets`, 306
      - `pylablib.core.gui.widgets.button`, 232
      - `pylablib.core.gui.widgets.button_selector`, 232
      - `pylablib.core.gui.widgets.combo_box`, 234
      - `pylablib.core.gui.widgets.container`, 235
      - `pylablib.core.gui.widgets.edit`, 274
      - `pylablib.core.gui.widgets.label`, 277
      - `pylablib.core.gui.widgets.layout_manager`, 279
      - `pylablib.core.gui.widgets.param_table`, 284
    - `pylablib.core.thread`, 371
      - `pylablib.core.thread.callsync`, 330
      - `pylablib.core.thread.controller`, 341
      - `pylablib.core.thread.multicast_pool`, 364
      - `pylablib.core.thread.notifier`, 366
      - `pylablib.core.thread.profile`, 366
      - `pylablib.core.thread.synchronizing`, 367
      - `pylablib.core.thread.threadprop`, 368
      - `pylablib.core.thread.utils`, 371
    - `pylablib.core.utils`, 455
      - `pylablib.core.utils.array_utils`, 371
      - `pylablib.core.utils.cext_tools`, 372
      - `pylablib.core.utils.crc`, 372
      - `pylablib.core.utils.ctypes_wrap`, 372
      - `pylablib.core.utils.dictionary`, 376
      - `pylablib.core.utils.files`, 412
      - `pylablib.core.utils.funcargparse`, 419
      - `pylablib.core.utils.functions`, 420
      - `pylablib.core.utils.general`, 425
      - `pylablib.core.utils.indexing`, 433
      - `pylablib.core.utils.ipc`, 435
      - `pylablib.core.utils.library_parameters`, 437
      - `pylablib.core.utils.module`, 437
      - `pylablib.core.utils.nbtools`, 439
      - `pylablib.core.utils.net`, 440
      - `pylablib.core.utils.numerical`, 444
      - `pylablib.core.utils.observer_pool`, 445
      - `pylablib.core.utils.py3`, 446
      - `pylablib.core.utils.rpyc_utils`, 446
      - `pylablib.core.utils.strdump`, 448
      - `pylablib.core.utils.string`, 449
      - `pylablib.core.utils.strpack`, 453
      - `pylablib.core.utils.units`, 454

pylablib.devices, 1034  
pylablib.devices.Agilent, 507  
pylablib.devices.Agilent.base, 505  
pylablib.devices.Agilent.pressure, 505  
pylablib.devices.AlliedVision, 522  
pylablib.devices.AlliedVision.Bonito, 507  
pylablib.devices.Andor, 550  
pylablib.devices.Andor.AndorSDK2, 522  
pylablib.devices.Andor.AndorSDK3, 534  
pylablib.devices.Andor.atcore\_features, 549  
pylablib.devices.Andor.base, 549  
pylablib.devices.Andor.Shamrock, 544  
pylablib.devices.Arcus, 563  
pylablib.devices.Arcus.base, 550  
pylablib.devices.Arcus.performax, 551  
pylablib.devices.Arduino, 566  
pylablib.devices.Arduino.base, 563  
pylablib.devices.Attocube, 574  
pylablib.devices.Attocube.anc300, 566  
pylablib.devices.Attocube.anc350, 570  
pylablib.devices.Attocube.base, 574  
pylablib.devices.AWG, 505  
pylablib.devices.AWG.generic, 455  
pylablib.devices.AWG.specific, 462  
pylablib.devices.Basler, 584  
pylablib.devices.Basler.pylon, 574  
pylablib.devices.BitFlow, 597  
pylablib.devices.BitFlow.BitFlow, 584  
pylablib.devices.Conrad, 599  
pylablib.devices.Conrad.base, 597  
pylablib.devices.Cryocon, 604  
pylablib.devices.Cryocon.base, 599  
pylablib.devices.Cryomagnetics, 613  
pylablib.devices.Cryomagnetics.base, 604  
pylablib.devices.DCAM, 621  
pylablib.devices.DCAM.DCAM, 613  
pylablib.devices.ElektroAutomatik, 625  
pylablib.devices.ElektroAutomatik.base, 621  
pylablib.devices.HighFinesse, 629  
pylablib.devices.HighFinesse.wlm, 625  
pylablib.devices.Hubner, 633  
pylablib.devices.Hubner.base, 633  
pylablib.devices.Hubner.Cobolt, 629  
pylablib.devices.IMAQ, 648  
pylablib.devices.IMAQ.IMAQ, 633  
pylablib.devices.IMAQ.niimaq\_attrtypes, 648  
pylablib.devices.IMAQdx, 663  
pylablib.devices.IMAQdx.IMAQdx, 648  
pylablib.devices.interface, 1022  
pylablib.devices.interface.camera, 989  
pylablib.devices.interface.stage, 1020  
pylablib.devices.Keithley, 671  
pylablib.devices.Keithley.base, 665  
pylablib.devices.Keithley.multimeter, 666  
pylablib.devices.KJL, 665  
pylablib.devices.KJL.base, 663  
pylablib.devices.Lakeshore, 682  
pylablib.devices.Lakeshore.base, 671  
pylablib.devices.LaserQuantum, 685  
pylablib.devices.LaserQuantum.base, 682  
pylablib.devices.Leybold, 689  
pylablib.devices.Leybold.base, 685  
pylablib.devices.LighthousePhotonics, 692  
pylablib.devices.LighthousePhotonics.base, 689  
pylablib.devices.Lumel, 695  
pylablib.devices.Lumel.base, 692  
pylablib.devices.M2, 707  
pylablib.devices.M2.base, 695  
pylablib.devices.M2.emm, 697  
pylablib.devices.M2.solstis, 701  
pylablib.devices.Mightex, 714  
pylablib.devices.Mightex.base, 714  
pylablib.devices.Mightex.MightexSSeries, 707  
pylablib.devices.Modbus, 717  
pylablib.devices.Modbus.modbus, 714  
pylablib.devices.Newport, 739  
pylablib.devices.Newport.base, 735  
pylablib.devices.Newport.picomotor, 736  
pylablib.devices.NI, 725  
pylablib.devices.NI.daq, 717  
pylablib.devices.NKT, 735  
pylablib.devices.NKT.interbus, 725  
pylablib.devices.Omron, 749  
pylablib.devices.Omron.base, 746  
pylablib.devices.Ophir, 754  
pylablib.devices.Ophir.base, 749  
pylablib.devices.OZOptics, 746  
pylablib.devices.OZOptics.base, 739  
pylablib.devices.PCO, 763  
pylablib.devices.PCO.SC2, 754  
pylablib.devices.Pfeiffer, 769  
pylablib.devices.Pfeiffer.base, 763  
pylablib.devices.Photometrics, 779  
pylablib.devices.Photometrics.pvcam, 769  
pylablib.devices.PhotonFocus, 813  
pylablib.devices.PhotonFocus.PhotonFocus, 779  
pylablib.devices.PhysikInstrumente, 824  
pylablib.devices.PhysikInstrumente.base, 813  
pylablib.devices.PrincetonInstruments, 833  
pylablib.devices.PrincetonInstruments.picam, 824  
pylablib.devices.Rigol, 838  
pylablib.devices.Rigol.base, 833  
pylablib.devices.Rigol.power\_supply, 834  
pylablib.devices.SiliconSoftware, 855  
pylablib.devices.SiliconSoftware.fgrab, 838  
pylablib.devices.Sirah, 868

- [pylablib.devices.Sirah.base](#), 864
- [pylablib.devices.Sirah.Matisse](#), 855
- [pylablib.devices.Sirah.tuner](#), 864
- [pylablib.devices.SmarAct](#), 876
- [pylablib.devices.SmarAct.base](#), 873
- [pylablib.devices.SmarAct.MCS2](#), 868
- [pylablib.devices.SmarAct.scu3d](#), 873
- [pylablib.devices.Standa](#), 880
- [pylablib.devices.Standa.base](#), 876
- [pylablib.devices.Tektronix](#), 902
- [pylablib.devices.Tektronix.base](#), 880
- [pylablib.devices.Thorlabs](#), 968
- [pylablib.devices.Thorlabs.base](#), 911
- [pylablib.devices.Thorlabs.elliptec](#), 911
- [pylablib.devices.Thorlabs.kinesis](#), 916
- [pylablib.devices.Thorlabs.misc](#), 945
- [pylablib.devices.Thorlabs.serial](#), 954
- [pylablib.devices.Thorlabs.TLCamera](#), 902
- [pylablib.devices.Toptica](#), 971
- [pylablib.devices.Toptica.base](#), 968
- [pylablib.devices.Toptica.ibeam](#), 968
- [pylablib.devices.Trinamic](#), 980
- [pylablib.devices.Trinamic.base](#), 971
- [pylablib.devices.uc480](#), 1031
- [pylablib.devices.uc480.uc480](#), 1022
- [pylablib.devices.utils](#), 1034
- [pylablib.devices.utils.color](#), 1031
- [pylablib.devices.utils.load\\_lib](#), 1032
- [pylablib.devices.Voltcraft](#), 987
- [pylablib.devices.Voltcraft.base](#), 980
- [pylablib.devices.Voltcraft.multimeter](#), 981
- [pylablib.devices.Windows](#), 989
- [pylablib.devices.Windows.joystick](#), 987
- [pylablib.widgets](#), 1034



## INDEX

### A

- `abort_autostart()` (py-lablib.devices.Hubner.Cobolt.Cobolt method), 630
- `accel` (pylablib.devices.Standa.base.TMoveParams attribute), 877
- `accel` (pylablib.devices.Trinamic.base.TVelocityParams attribute), 971
- `acceleration` (pylablib.devices.SmarAct.MCS2.TCLMoveParams attribute), 869
- `acceleration` (pylablib.devices.Thorlabs.kinesis.TJogParams attribute), 919
- `acceleration` (pylablib.devices.Thorlabs.kinesis.TPZMotorDriveParams attribute), 920
- `acceleration` (pylablib.devices.Thorlabs.kinesis.TPZMotorJogParams attribute), 921
- `acceleration` (pylablib.devices.Thorlabs.kinesis.TVelocityParams attribute), 919
- `access` (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576
- `AccessIterator` (class in pylablib.core.utils.general), 432
- `accum_cycle_time` (py-lablib.devices.Andor.AndorSDK2.TCycleTimings attribute), 523
- `acknowledge()` (pylablib.core.utils.general.Timer method), 430
- `acqcleared()` (in module py-lablib.devices.interface.camera), 994
- `acqstopped()` (in module py-lablib.devices.interface.camera), 994
- `acquire()` (pylablib.core.thread.synchronizing.QLockNotifier method), 368
- `acquired` (pylablib.devices.interface.camera.TFramesStatus attribute), 989
- `acquired` (pylablib.devices.uc480.uc480.TAcquiredFramesStatus attribute), 1023
- `acquisition_in_progress()` (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 513
- `acquisition_in_progress()` (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 509
- `acquisition_in_progress()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 524
- `acquisition_in_progress()` (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 540
- `acquisition_in_progress()` (py-lablib.devices.Basler.pylon.BaslerPylonCamera method), 580
- `acquisition_in_progress()` (py-lablib.devices.BitFlow.BitFlow.BitFlowCamera method), 591
- `acquisition_in_progress()` (py-lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 587
- `acquisition_in_progress()` (py-lablib.devices.DCAM.DCAM.DCAMCamera method), 618
- `acquisition_in_progress()` (py-lablib.devices.IMAQ.IMAQ.IMAQCamera method), 641
- `acquisition_in_progress()` (py-lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 637
- `acquisition_in_progress()` (py-lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 657
- `acquisition_in_progress()` (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 653
- `acquisition_in_progress()` (py-lablib.devices.interface.camera.IAttributeCamera method), 996
- `acquisition_in_progress()` (py-lablib.devices.interface.camera.IBinROICamera method), 1015
- `acquisition_in_progress()` (py-lablib.devices.interface.camera.ICamera method), 990
- `acquisition_in_progress()` (py-lablib.devices.interface.camera.IExposureCamera method), 990

method), 1006

acquisition\_in\_progress() (py-lablib.devices.interface.camera.IGrabberAttribute method), 1001

acquisition\_in\_progress() (py-lablib.devices.interface.camera.IROICamera method), 1011

acquisition\_in\_progress() (py-lablib.devices.Mightex.MightexSSeries.MightexSSeries method), 710

acquisition\_in\_progress() (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 758

acquisition\_in\_progress() (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 775

acquisition\_in\_progress() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus method), 784

acquisition\_in\_progress() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 806

acquisition\_in\_progress() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 788

acquisition\_in\_progress() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 798

acquisition\_in\_progress() (py-lablib.devices.PrincetonInstruments.picam.Picam method), 830

acquisition\_in\_progress() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera method), 849

acquisition\_in\_progress() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 844

acquisition\_in\_progress() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 907

acquisition\_in\_progress() (py-lablib.devices.uc480.uc480.UC480Camera method), 1027

activation\_control (py-lablib.devices.Pfeiffer.base.TTPG260GaugeControl attribute), 764

add() (pylablib.core.dataproc.filters.RunningDebounceFilter method), 140

add() (pylablib.core.dataproc.filters.RunningDecimationFilter method), 140

add\_all\_children() (py-lablib.core.gui.value\_handling.GUIValues method), 327

add\_attribute() (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 537

add\_background\_comm() (py-lablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 917

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.KinesisDevice method), 921

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 932

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 936

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943

add\_background\_comm() (py-lablib.devices.Thorlabs.kinesis.MFF method), 925

add\_background\_job() (py-lablib.core.thread.controller.QTaskThread method), 352

add\_button() (pylablib.core.gui.widgets.param\_table.ParamTable method), 287

add\_button() (pylablib.core.gui.widgets.param\_table.StatusTable method), 296

add\_button\_selector() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 291

add\_button\_selector() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 296

add\_callback() (pylablib.core.thread.callsync.QScheduledCall method), 332

add\_check\_box() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 288

add\_check\_box() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 297

add\_child() (pylablib.core.gui.widgets.container.IQContainer method), 237

add\_child() (pylablib.core.gui.widgets.container.IQWidgetContainer method), 241

add\_child() (pylablib.core.gui.widgets.container.QContainer method), 238

add\_child() (pylablib.core.gui.widgets.container.QDialogContainer



method), 255

add\_child() (pylablib.core.gui.widgets.container.QFrameAddChild method), 250

add\_child() (pylablib.core.gui.widgets.container.QGroupBoxAddChild method), 260

add\_child() (pylablib.core.gui.widgets.container.QScrollAreaAddChild method), 269

add\_child() (pylablib.core.gui.widgets.container.QScrollAreaAddChild method), 264

add\_child() (pylablib.core.gui.widgets.container.QTabContainerAddChild method), 272

add\_child() (pylablib.core.gui.widgets.container.QWidgetContainerAddChild method), 246

add\_child() (pylablib.core.gui.widgets.param\_table.ParamTableAddChild method), 292

add\_child() (pylablib.core.gui.widgets.param\_table.StatusTableAddChild method), 297

add\_child\_values() (py-lablib.core.gui.widgets.container.IQContainerAddChildValues method), 236

add\_child\_values() (py-lablib.core.gui.widgets.container.IQWidgetContainerAddChildValues method), 242

add\_child\_values() (py-lablib.core.gui.widgets.container.QContainerAddChildValues method), 238

add\_child\_values() (py-lablib.core.gui.widgets.container.QDialogContainerAddChildValues method), 255

add\_child\_values() (py-lablib.core.gui.widgets.container.QFrameContainerAddChildValues method), 251

add\_child\_values() (py-lablib.core.gui.widgets.container.QGroupBoxContainerAddChildValues method), 260

add\_child\_values() (py-lablib.core.gui.widgets.container.QScrollAreaContainerAddChildValues method), 269

add\_child\_values() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainerAddChildValues method), 265

add\_child\_values() (py-lablib.core.gui.widgets.container.QWidgetContainerAddChildValues method), 272

add\_child\_values() (py-lablib.core.gui.widgets.container.QWidgetContainerAddChildValues method), 246

add\_child\_values() (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidgetAddChildValues method), 281

add\_child\_values() (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidgetAddChildValues method), 282

add\_child\_values() (py-lablib.core.gui.widgets.param\_table.ParamTableAddChildValues method), 293

add\_child\_values() (py-lablib.core.gui.widgets.param\_table.StatusTableAddChildValues method), 297

add\_chunk() (pylablib.core.fileio.parse\_csv.ChunksAccumulatorAddChunk method), 223

add\_class() (pylablib.core.utils.strdump.StrDumperAddClass method), 448

add\_clock\_period\_input() (py-lablib.devices.NI.daq.NIDAQAddClockPeriodInput method), 720

add\_columns() (pylablib.core.fileio.parse\_csv.ChunksAccumulatorAddColumns method), 223

add\_combo\_box() (py-lablib.core.gui.widgets.param\_table.ParamTableAddComboBox method), 290

add\_combo\_box() (py-lablib.core.gui.widgets.param\_table.StatusTableAddComboBox method), 297

add\_command() (pylablib.core.thread.controller.QTaskThreadAddCommand method), 354

add\_conversion\_class() (in module py-lablib.core.utils.string), 451

add\_counter\_input() (py-lablib.devices.NI.daq.NIDAQAddCounterInput method), 719

add\_custom\_widget() (py-lablib.core.gui.widgets.param\_table.ParamTableAddCustomWidget method), 286

add\_custom\_widget() (py-lablib.core.gui.widgets.param\_table.StatusTableAddCustomWidget method), 298

add\_decoration\_label() (py-lablib.core.gui.widgets.container.IQWidgetContainerAddDecorationLabel method), 242

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QDialogContainerAddDecorationLabel method), 255

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QFrameContainerAddDecorationLabel method), 251

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QGroupBoxContainerAddDecorationLabel method), 260

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QScrollAreaContainerAddDecorationLabel method), 269

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainerAddDecorationLabel method), 265

add\_decoration\_label() (py-lablib.core.gui.widgets.container.QWidgetContainerAddDecorationLabel method), 246

add\_decoration\_label() (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidgetAddDecorationLabel method), 281

add\_decoration\_label() (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidgetAddDecorationLabel method), 282

add\_decoration\_label() (py-lablib.core.gui.widgets.param\_table.ParamTableAddDecorationLabel method), 293

add\_decoration\_label() (py-lablib.core.gui.widgets.param\_table.StatusTableAddDecorationLabel method), 297

- method*), 298
- `add_dict_entry_builder()` (in module `pylablib.core.fileio.dict_entry`), 203
- `add_dict_entry_class()` (in module `pylablib.core.fileio.dict_entry`), 204
- `add_dict_entry_parser()` (in module `pylablib.core.fileio.dict_entry`), 203
- `add_digital_input()` (`pylablib.devices.NI.daq.NIDAQ` method), 720
- `add_digital_output()` (`pylablib.devices.NI.daq.NIDAQ` method), 721
- `add_direct_call_command()` (`pylablib.core.thread.controller.QTaskThread` method), 354
- `add_dropdown_button()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 287
- `add_dropdown_button()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 298
- `add_entry()` (`pylablib.core.utils.dictionary.Dictionary` method), 377
- `add_entry()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 386
- `add_entry()` (`pylablib.core.utils.dictionary.FilterTree` method), 403
- `add_entry()` (`pylablib.core.utils.dictionary.PrefixTree` method), 395
- `add_enum_label()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 288
- `add_enum_label()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 299
- `add_exception_hook()` (in module `pylablib.core.thread.controller`), 341
- `add_file_format()` (`pylablib.core.fileio.dict_entry.ExternalNumpyDictionaryEntry` static method), 209
- `add_file_format()` (`pylablib.core.fileio.dict_entry.IExternalFileDictionaryEntry` static method), 208
- `add_frame()` (`pylablib.core.gui.widgets.container.IQWidgetContainer` method), 241
- `add_frame()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 255
- `add_frame()` (`pylablib.core.gui.widgets.container.QFrameContainer` method), 251
- `add_frame()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer` method), 260
- `add_frame()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainer` method), 265
- `add_frame()` (`pylablib.core.gui.widgets.container.QWidgetContainer` method), 246
- `add_frame()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 285
- `add_frame()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 299
- `add_handler()` (`pylablib.core.gui.value_handling.GUIValues` method), 327
- `add_indicator_handler()` (`pylablib.core.gui.value_handling.GUIValues` method), 328
- `add_job()` (`pylablib.core.thread.controller.QTaskThread` method), 352
- `add_label_indicator()` (`pylablib.core.gui.value_handling.GUIValues` method), 328
- `add_namedtuple_class()` (in module `pylablib.core.utils.string`), 451
- `add_nested()` (`pylablib.core.gui.value_handling.GUIValues` method), 327
- `add_note()` (`pylablib.core.devio.base.DeviceError` method), 170
- `add_note()` (`pylablib.core.devio.comm_backend.DeviceBackendError` method), 170
- `add_note()` (`pylablib.core.devio.comm_backend.DeviceFT232Error` method), 178
- `add_note()` (`pylablib.core.devio.comm_backend.DeviceHIDError` method), 186
- `add_note()` (`pylablib.core.devio.comm_backend.DeviceNetworkError` method), 181
- `add_note()` (`pylablib.core.devio.comm_backend.DeviceRecordedError` method), 189



`add_note()` (pylablib.core.devio.comm\_backend.DeviceSerialError method), 175  
`add_note()` (pylablib.core.devio.comm\_backend.DeviceUSBError method), 183  
`add_note()` (pylablib.core.devio.comm\_backend.DeviceVisaError method), 172  
`add_note()` (pylablib.core.devio.hid\_base.HIDError method), 196  
`add_note()` (pylablib.core.devio.hid\_base.HIDLibError method), 196  
`add_note()` (pylablib.core.devio.hid\_base.HIDTimeoutError method), 196  
`add_note()` (pylablib.core.gui.limiter.LimitError method), 308  
`add_note()` (pylablib.core.gui.value\_handling.MissingGUIValueError method), 326  
`add_note()` (pylablib.core.gui.value\_handling.NoParametersError method), 311  
`add_note()` (pylablib.core.thread.threadprop.DuplicateConnectionError method), 369  
`add_note()` (pylablib.core.thread.threadprop.InterruptException method), 370  
`add_note()` (pylablib.core.thread.threadprop.InterruptException method), 370  
`add_note()` (pylablib.core.thread.threadprop.NoControllerFoundError method), 369  
`add_note()` (pylablib.core.thread.threadprop.NoMessageThreadError method), 370  
`add_note()` (pylablib.core.thread.threadprop.SkippedCallError method), 370  
`add_note()` (pylablib.core.thread.threadprop.ThreadError method), 368  
`add_note()` (pylablib.core.thread.threadprop.TimeoutThreadError method), 369  
`add_note()` (pylablib.core.utils.net.SocketError method), 440  
`add_note()` (pylablib.core.utils.net.SocketTimeoutError method), 440  
`add_note()` (pylablib.devices.Agilent.base.AgilentBackendError method), 505  
`add_note()` (pylablib.devices.Agilent.base.AgilentError method), 505  
`add_note()` (pylablib.devices.AlliedVision.Bonito.BonitoError method), 507  
`add_note()` (pylablib.devices.Andor.base.AndorError method), 549  
`add_note()` (pylablib.devices.Andor.base.AndorFrameTransferError method), 550  
`add_note()` (pylablib.devices.Andor.base.AndorNotSupportedError method), 550  
`add_note()` (pylablib.devices.Andor.base.AndorTimeoutError method), 549  
`add_note()` (pylablib.devices.Arcus.base.ArcusBackendError method), 550  
`add_note()` (pylablib.devices.Arcus.base.ArcusError method), 550  
`add_note()` (pylablib.devices.Arduino.base.ArduinoBackendError method), 564  
`add_note()` (pylablib.devices.Arduino.base.ArduinoError method), 563  
`add_note()` (pylablib.devices.Attocube.base.AttocubeBackendError method), 574  
`add_note()` (pylablib.devices.Attocube.base.AttocubeError method), 574  
`add_note()` (pylablib.devices.AWG.generic.GenericAWGBackendError method), 455  
`add_note()` (pylablib.devices.AWG.generic.GenericAWGError method), 455  
`add_note()` (pylablib.devices.BitFlow.BitFlow.BitFlowError method), 584  
`add_note()` (pylablib.devices.BitFlow.BitFlow.BitFlowTimeoutError method), 585  
`add_note()` (pylablib.devices.Conrad.base.ConradBackendError method), 597  
`add_note()` (pylablib.devices.Conrad.base.ConradError method), 597  
`add_note()` (pylablib.devices.Cryocon.base.CryoconBackendError method), 599  
`add_note()` (pylablib.devices.Cryocon.base.CryoconError method), 599  
`add_note()` (pylablib.devices.Cryomagnetics.base.CryomagneticsBackendError method), 604  
`add_note()` (pylablib.devices.Cryomagnetics.base.CryomagneticsError method), 604  
`add_note()` (pylablib.devices.ElektroAutomatik.base.ElektroAutomatikBackendError method), 622  
`add_note()` (pylablib.devices.ElektroAutomatik.base.ElektroAutomatikError method), 622  
`add_note()` (pylablib.devices.Hubner.base.HubnerBackendError method), 633  
`add_note()` (pylablib.devices.Hubner.base.HubnerError method), 633  
`add_note()` (pylablib.devices.interface.camera.DefaultFrameTransferError method), 989  
`add_note()` (pylablib.devices.Keithley.base.GenericKeithleyBackendError method), 665  
`add_note()` (pylablib.devices.Keithley.base.GenericKeithleyError method), 665  
`add_note()` (pylablib.devices.KJL.base.KJLBackendError method), 663  
`add_note()` (pylablib.devices.KJL.base.KJLError method), 663  
`add_note()` (pylablib.devices.Lakeshore.base.LakeshoreBackendError method), 671  
`add_note()` (pylablib.devices.Lakeshore.base.LakeshoreError method), 671  
`add_note()` (pylablib.devices.LaserQuantum.base.LaserQuantumBackendError method), 682

`add_note()` (pylablib.devices.LaserQuantum.base.LaserQuantumBackendError method), 682

`add_note()` (pylablib.devices.Leybold.base.LeyboldBackendError method), 685

`add_note()` (pylablib.devices.Leybold.base.LeyboldError method), 685

`add_note()` (pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsBackendError method), 689

`add_note()` (pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsError method), 689

`add_note()` (pylablib.devices.M2.base.M2CommunicationError method), 695

`add_note()` (pylablib.devices.M2.base.M2Error method), 695

`add_note()` (pylablib.devices.M2.base.M2ParseError method), 695

`add_note()` (pylablib.devices.Mightex.base.MightexError method), 714

`add_note()` (pylablib.devices.Mightex.base.MightexTimeoutError method), 714

`add_note()` (pylablib.devices.Modbus.modbus.ModbusBackendError method), 715

`add_note()` (pylablib.devices.Modbus.modbus.ModbusError method), 714

`add_note()` (pylablib.devices.Newport.base.NewportBackendError method), 735

`add_note()` (pylablib.devices.Newport.base.NewportError method), 735

`add_note()` (pylablib.devices.NI.daq.NIDAQmxError method), 717

`add_note()` (pylablib.devices.NI.daq.NIError method), 717

`add_note()` (pylablib.devices.NKT.interbus.InterbusBackendError method), 725

`add_note()` (pylablib.devices.NKT.interbus.InterbusError method), 725

`add_note()` (pylablib.devices.Ophir.base.OphirBackendError method), 749

`add_note()` (pylablib.devices.Ophir.base.OphirError method), 749

`add_note()` (pylablib.devices.OZOptics.base.OZOpticsBackendError method), 740

`add_note()` (pylablib.devices.OZOptics.base.OZOpticsError method), 739

`add_note()` (pylablib.devices.Pfeiffer.base.PfeifferBackendError method), 764

`add_note()` (pylablib.devices.Pfeiffer.base.PfeifferError method), 763

`add_note()` (pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteBackendError method), 814

`add_note()` (pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteError method), 814

`add_note()` (pylablib.devices.Rigol.base.GenericRigolBackendError method), 834

`add_note()` (pylablib.devices.Rigol.base.GenericRigolError method), 833

`add_note()` (pylablib.devices.Sirah.base.GenericSirahBackendError method), 864

`add_note()` (pylablib.devices.Sirah.base.GenericSirahError method), 864

`add_note()` (pylablib.devices.Sirah.tuner.FrequencyReadSirahError method), 864

`add_note()` (pylablib.devices.SmarAct.base.SmarActError method), 873

`add_note()` (pylablib.devices.Standa.base.StandaBackendError method), 876

`add_note()` (pylablib.devices.Standa.base.StandaError method), 876

`add_note()` (pylablib.devices.Tektronix.base.TektronixBackendError method), 881

`add_note()` (pylablib.devices.Tektronix.base.TektronixError method), 880

`add_note()` (pylablib.devices.Thorlabs.base.ThorlabsBackendError method), 911

`add_note()` (pylablib.devices.Thorlabs.base.ThorlabsError method), 911

`add_note()` (pylablib.devices.Thorlabs.base.ThorlabsTimeoutError method), 911

`add_note()` (pylablib.devices.Toptica.base.TopticaBackendError method), 968

`add_note()` (pylablib.devices.Toptica.base.TopticaError method), 968

`add_note()` (pylablib.devices.Trinamic.base.TrinamicBackendError method), 971

`add_note()` (pylablib.devices.Trinamic.base.TrinamicError method), 971

`add_note()` (pylablib.devices.Trinamic.base.TrinamicTimeoutError method), 971

`add_note()` (pylablib.devices.Voltcraft.base.GenericVoltcraftBackendError method), 980

`add_note()` (pylablib.devices.Voltcraft.base.GenericVoltcraftError method), 980

`add_note()` (pylablib.devices.Voltcraft.multimeter.VC880ParseError method), 984

`add_num_edit()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 290

`add_num_edit()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 299

`add_num_label()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 289

`add_num_label()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 300

`add_observer()` (pylablib.core.utils.observer\_pool.ObserverPool method), 445

`add_padding()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 242

`add_padding()` (pylablib.core.gui.widgets.container.QDialogContainer method), 256  
`add_padding()` (pylablib.core.gui.widgets.container.QFrameContainer method), 251  
`add_padding()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 260  
`add_padding()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 265  
`add_padding()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 246  
`add_padding()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 281  
`add_padding()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 282  
`add_padding()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 411  
`add_padding()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 293  
`add_padding()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 300  
`add_path()` (pylablib.core.utils.general.StreamFileLogger method), 431  
`add_progress_bar()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 290  
`add_progress_bar()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 300  
`add_property_element()` (pylablib.core.gui.value\_handling.GUIValues method), 327  
`add_property_element()` (pylablib.core.gui.widgets.container.IQContainer method), 237  
`add_property_element()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 242  
`add_property_element()` (pylablib.core.gui.widgets.container.QContainer method), 239  
`add_property_element()` (pylablib.core.gui.widgets.container.QDialogContainer method), 256  
`add_property_element()` (pylablib.core.gui.widgets.container.QFrameContainer method), 251  
`add_property_element()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 261  
`add_property_element()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 265  
`add_property_element()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 247  
`add_property_element()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 281  
`add_property_element()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 282  
`add_property_element()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 293  
`add_property_element()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 301  
`add_property_element()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 296  
`add_property_element()` (pylablib.core.thread.controller.QTaskThread method), 356  
`add_property_element()` (pylablib.core.thread.controller.QThreadController method), 349  
`add_property_element()` (pylablib.core.utils.general.StreamFileLogger method), 431  
`add_property_element()` (pylablib.core.gui.widgets.container.QTabContainer method), 272  
`add_property_element()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 247  
`add_property_element()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 287  
`add_property_element()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 411  
`add_pulse_output()` (pylablib.devices.NI.daq.NIDAQ method), 411  
`add_shortcut()` (pylablib.core.utils.dictionary.PrefixShortcutTree method), 411  
`add_shortcuts()` (pylablib.core.utils.dictionary.PrefixShortcutTree method), 411  
`add_simple_widget()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 286  
`add_simple_widget()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 300  
`add_spacer()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 242  
`add_spacer()` (pylablib.core.gui.widgets.container.QDialogContainer method), 256  
`add_spacer()` (pylablib.core.gui.widgets.container.QFrameContainer method), 251  
`add_spacer()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 261  
`add_spacer()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 265  
`add_spacer()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 247  
`add_spacer()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 281  
`add_spacer()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 282  
`add_spacer()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 293  
`add_spacer()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 301  
`add_status_line()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 296  
`add_stop_notifier()` (pylablib.core.thread.controller.QTaskThread method), 356  
`add_stop_notifier()` (pylablib.core.thread.controller.QThreadController method), 349  
`add_stream()` (pylablib.core.utils.general.StreamFileLogger method), 431

<i>method</i> ), 431	<i>add_thread_method()</i> (py-	<i>lablib.core.thread.controller.QThreadController</i>
<i>add_style_indicator_label()</i> (py-	<i>lablib.core.gui.widgets.param_table.ParamTable</i>	<i>method</i> ), 347
<i>method</i> ), 289	<i>add_time()</i> (pylablib.core.utils.general.Countdown	<i>method</i> ), 430
<i>add_style_indicator_label()</i> (py-	<i>lablib.core.gui.widgets.param_table.StatusTable</i>	<i>add_timer()</i> (pylablib.core.gui.widgets.container.IQContainer
<i>method</i> ), 301	<i>method</i> ), 236	<i>add_timer()</i> (pylablib.core.gui.widgets.container.IQWidgetContainer
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.IQWidgetContainer</i>	<i>method</i> ), 242
<i>method</i> ), 242	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QContainer	<i>method</i> ), 239
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.QDialogContainer</i>	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QDialogContainer
<i>method</i> ), 256	<i>method</i> ), 256	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QFrameContainer
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.QFrameContainer</i>	<i>method</i> ), 251
<i>method</i> ), 251	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QGroupBoxContainer	<i>method</i> ), 261
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.QGroupBoxContainer</i>	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QScrollAreaContainer
<i>method</i> ), 261	<i>method</i> ), 270	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QScrollAreaContainer.Q
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.QScrollAreaContainer.QContainerWidget</i>	<i>method</i> ), 265
<i>method</i> ), 265	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QTabContainer	<i>method</i> ), 272
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.container.QWidgetContainer</i>	<i>add_timer()</i> (pylablib.core.gui.widgets.container.QWidgetContainer
<i>method</i> ), 247	<i>method</i> ), 247	<i>add_timer()</i> (pylablib.core.gui.widgets.param_table.ParamTable
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget</i>	<i>method</i> ), 293
<i>method</i> ), 280	<i>add_timer()</i> (pylablib.core.gui.widgets.param_table.StatusTable	<i>method</i> ), 302
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.layout_manager.QLayoutManagedWidget</i>	<i>add_timer_event()</i> (py-
<i>method</i> ), 282	<i>method</i> ), 236	<i>lablib.core.gui.widgets.container.IQContainer</i>
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.param_table.ParamTable</i>	<i>add_timer_event()</i> (py-
<i>method</i> ), 285	<i>method</i> ), 242	<i>lablib.core.gui.widgets.container.IQWidgetContainer</i>
<i>add_sublayout()</i> (py-	<i>lablib.core.gui.widgets.param_table.StatusTable</i>	<i>add_timer_event()</i> (py-
<i>method</i> ), 301	<i>method</i> ), 239	<i>lablib.core.gui.widgets.container.QContainer</i>
<i>add_tab()</i> (pylablib.core.gui.widgets.container.QTabContainer	<i>method</i> ), 239	<i>add_timer_event()</i> (py-
<i>method</i> ), 271	<i>add_timer_event()</i> (py-	<i>lablib.core.gui.widgets.container.QDialogContainer</i>
<i>add_text_edit()</i> (py-	<i>method</i> ), 256	<i>add_timer_event()</i> (py-
<i>lablib.core.gui.widgets.param_table.ParamTable</i>	<i>method</i> ), 252	<i>lablib.core.gui.widgets.container.QFrameContainer</i>
<i>method</i> ), 289	<i>method</i> ), 252	<i>add_timer_event()</i> (py-
<i>add_text_edit()</i> (py-	<i>lablib.core.gui.widgets.param_table.StatusTable</i>	<i>method</i> ), 261
<i>method</i> ), 302	<i>method</i> ), 270	<i>add_timer_event()</i> (py-
<i>add_text_label()</i> (py-	<i>lablib.core.gui.widgets.param_table.ParamTable</i>	<i>method</i> ), 266
<i>method</i> ), 288	<i>method</i> ), 266	<i>add_timer_event()</i> (py-
<i>add_text_label()</i> (py-	<i>lablib.core.gui.widgets.param_table.StatusTable</i>	<i>method</i> ), 266
<i>method</i> ), 302	<i>method</i> ), 266	<i>add_timer_event()</i> (py-
<i>add_thread_method()</i> (py-	<i>lablib.core.thread.controller.QTaskThread</i>	<i>method</i> ), 266
<i>method</i> ), 356	<i>method</i> ), 266	<i>add_timer_event()</i> (py-



`lablib.core.gui.widgets.container.QTabContainer` method), 273  
`add_timer_event()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer` method), 247  
`add_timer_event()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` method), 293  
`add_timer_event()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` method), 302  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.IQWidgetContainer` method), 243  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QDialogContainer` method), 256  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QFrameContainer` method), 252  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QGroupBoxContainer` method), 261  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer` method), 270  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer` method), 266  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QTabContainer` method), 266  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer.QWidget` method), 247  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer` method), 247  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` method), 286  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget` method), 280  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` method), 303  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.layout_manager.QLayoutManagedWidget` method), 282  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` method), 293  
`add_to_layout()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` method), 302  
`add_toggle_button()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` method), 287  
`add_toggle_button()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` method), 302  
`add_variable()` (pylablib.core.utils.ipc.SharedMemIPCThread method), 436  
`add_virtual_element()` (py-  
`lablib.core.gui.value_handling.GUIValues` method), 327  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.IQContainer` method), 237  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.IQWidgetContainer` method), 243  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QContainer` method), 239  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QDialogContainer` method), 256  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QFrameContainer` method), 252  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QGroupBoxContainer` method), 261  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer` method), 270  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer` method), 266  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QTabContainer` method), 266  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer.QWidget` method), 247  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer` method), 247  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` method), 286  
`add_virtual_element()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` method), 303  
`add_voltage_input()` (py-  
`lablib.devices.NI.daq.NIDAQ` method), 719  
`add_voltage_output()` (py-  
`lablib.devices.NI.daq.NIDAQ` method), 722  
`add_widget()` (pylablib.core.gui.value\_handling.GUIValues method), 327  
`add_widget_indicator()` (py-  
`lablib.core.gui.value_handling.GUIValues` method), 328  
`added` (pylablib.core.utils.dictionary.DictionaryDiff attribute), 385  
`addr` (pylablib.devices.Conrad.base.RelayBoard.TMessage attribute), 598  
`addr` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor.CommData attribute), 913  
`addr` (pylablib.devices.Trinamic.base.TTMCM1110ReplyData attribute), 972  
`address` (pylablib.devices.Attocube.anc350.ANC350.Reply attribute), 570  
`address` (pylablib.devices.Attocube.anc350.ANC350.Telegram

- attribute*), 570
- `address` (*pylablib.devices.Modbus.modbus.TModbusFrame*  
*attribute*), 715
- `advance_read_frames()` (*py-*  
*lablib.devices.interface.camera.FrameCounter*  
*method*), 995
- `Agilent33220A` (*class in py-*  
*lablib.devices.AWG.specific*), 468
- `Agilent33500` (*class in pylablib.devices.AWG.specific*),  
462
- `AgilentBackendError`, 505
- `AgilentError`, 505
- `ai1()` (*in module pylablib.core.utils.nbtools*), 439
- `ai2()` (*in module pylablib.core.utils.nbtools*), 439
- `ai4()` (*in module pylablib.core.utils.nbtools*), 439
- `ai8()` (*in module pylablib.core.utils.nbtools*), 439
- `allocate()` (*pylablib.devices.interface.camera.ChunkBufferManager*  
*method*), 995
- `allocate()` (*pylablib.devices.Mightex.MightexSSeries.MightexSSeries.ChunkData.ReceiveLooper*  
*method*), 710
- `allocate()` (*pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus.SiFCam.BufferManager*  
*method*), 797
- `allocate()` (*pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware.fgrab.ChunkData.ReceiveLooper*  
*method*), 848
- `allocate()` (*pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware.fgrab.ChunkData.ReceiveLooper*  
*method*), 843
- `allocate_buffers()` (*py-*  
*lablib.devices.Andor.AndorSDK3.AndorSDK3Camera.BufferManager*  
*method*), 539
- `allowing_toploop()` (*py-*  
*lablib.core.thread.controller.QTaskThread*  
*method*), 356
- `allowing_toploop()` (*py-*  
*lablib.core.thread.controller.QThreadController*  
*method*), 342
- `amp1` (*pylablib.devices.Sirah.Matisse.TPiezoetFeedforwardParameters*  
*attribute*), 855
- `amplitude` (*pylablib.devices.Sirah.Matisse.TPiezoetDriveParameters*  
*attribute*), 855
- `amplitude` (*pylablib.devices.SmarAct.MCS2.TStepMoveParams*  
*attribute*), 869
- `ANC300` (*class in pylablib.devices.Attocube.anc300*), 566
- `ANC350` (*class in pylablib.devices.Attocube.anc350*), 570
- `ANC350.Reply` (*class in py-*  
*lablib.devices.Attocube.anc350*), 570
- `ANC350.Telegram` (*class in py-*  
*lablib.devices.Attocube.anc350*), 570
- `AndorError`, 549
- `AndorFrameTransferError`, 550
- `AndorNotSupportedError`, 550
- `AndorSDK2Camera` (*class in py-*  
*lablib.devices.Andor.AndorSDK2*), 523
- `AndorSDK3Attribute` (*class in py-*  
*lablib.devices.Andor.AndorSDK3*), 534
- `AndorSDK3Camera` (*class in py-*  
*lablib.devices.Andor.AndorSDK3*), 536
- `AndorSDK3Camera.BufferManager` (*class in py-*  
*lablib.devices.Andor.AndorSDK3*), 539
- `AndorTimeoutError`, 549
- `angular_deviation` (*py-*  
*lablib.devices.Andor.Shamrock.TOpticalParameters*  
*attribute*), 544
- `antiplay` (*pylablib.devices.Standa.base.TMoveParams*  
*attribute*), 877
- `any_item()` (*in module pylablib.core.utils.general*), 426
- `aperture` (*pylablib.devices.Keithley.multimeter.TFrequencyFunctionParam*  
*attribute*), 666
- `append()` (*pylablib.core.dataproc.table\_wrap.Array1DWrapper*  
*method*), 154
- `append()` (*pylablib.core.dataproc.table\_wrap.Array2DWrapper.ColumnAccess*  
*method*), 154
- `append()` (*pylablib.core.dataproc.table\_wrap.Array2DWrapper.RowAccess*  
*method*), 154
- `append()` (*pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper.ColumnAccess*  
*method*), 154
- `append()` (*pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper.RowAccess*  
*method*), 154
- `applet_info` (*pylablib.devices.SiliconSoftware.fgrab.TDeviceInfo*  
*attribute*), 848
- `apply_calibration()` (*py-*  
*lablib.devices.Sirah.tuner.MatisseTuner*  
*method*), 865
- `apply_settings()` (*py-*  
*lablib.core.devio.comm\_backend.ICommBackendWrapper*  
*method*), 192
- `apply_settings()` (*py-*  
*lablib.core.devio.interface.IDevice* *method*),  
197
- `apply_settings()` (*py-*  
*lablib.core.devio.SCPI.SCPIDevice* *method*),  
169
- `apply_settings()` (*py-*  
*lablib.devices.Agilent.pressure.XGS600*  
*method*), 506
- `apply_settings()` (*py-*  
*lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera*  
*method*), 513
- `apply_settings()` (*py-*  
*lablib.devices.AlliedVision.Bonito.IBonitoCamera*  
*method*), 509
- `apply_settings()` (*py-*  
*lablib.devices.Andor.AndorSDK2.AndorSDK2Camera*  
*method*), 530
- `apply_settings()` (*py-*  
*lablib.devices.Andor.AndorSDK3.AndorSDK3Camera*  
*method*), 540
- `apply_settings()` (*py-*  
*lablib.devices.Andor.Shamrock.ShamrockSpectrograph*  
*method*), 540

<i>method</i> ), 548	<i>method</i> ), 587
<code>apply_settings()</code> <i>lablib.devices.Arcus.performax.GenericPerformaxStage</i> <i>method</i> ), 552	<code>apply_settings()</code> <i>lablib.devices.Conrad.base.RelayBoard</i> <i>method</i> ), 598
<code>apply_settings()</code> <i>lablib.devices.Arcus.performax.Performax2EXStage</i> <i>method</i> ), 557	<code>apply_settings()</code> <i>lablib.devices.Cryocon.base.Cryocon1x</i> <i>method</i> ), 601
<code>apply_settings()</code> <i>lablib.devices.Arcus.performax.Performax4EXStage</i> <i>method</i> ), 555	<code>apply_settings()</code> <i>lablib.devices.Cryomagnetics.base.LM500</i> <i>method</i> ), 605
<code>apply_settings()</code> <i>lablib.devices.Arcus.performax.PerformaxDMXJSASStage</i> <i>method</i> ), 562	<code>apply_settings()</code> <i>lablib.devices.Cryomagnetics.base.LM510</i> <i>method</i> ), 609
<code>apply_settings()</code> <i>lablib.devices.Arduino.base.IArduinoDevice</i> <i>method</i> ), 565	<code>apply_settings()</code> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 618
<code>apply_settings()</code> <i>lablib.devices.Attocube.anc300.ANC300</i> <i>method</i> ), 568	<code>apply_settings()</code> <i>lablib.devices.ElektroAutomatik.base.PS2000B</i> <i>method</i> ), 624
<code>apply_settings()</code> <i>lablib.devices.Attocube.anc350.ANC350</i> <i>method</i> ), 572	<code>apply_settings()</code> <i>lablib.devices.HighFinesse.wlm.WLM</i> <i>method</i> ), 629
<code>apply_settings()</code> <i>lablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 459	<code>apply_settings()</code> <i>lablib.devices.Hubner.Cobolt.Cobolt</i> <i>method</i> ), 632
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 468	<code>apply_settings()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 641
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 462	<code>apply_settings()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 637
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 480	<code>apply_settings()</code> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 657
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 474	<code>apply_settings()</code> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 653
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 499	<code>apply_settings()</code> <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 996
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 486	<code>apply_settings()</code> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1015
<code>apply_settings()</code> <i>lablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 493	<code>apply_settings()</code> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 993
<code>apply_settings()</code> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 581	<code>apply_settings()</code> <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1006
<code>apply_settings()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 591	<code>apply_settings()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1001
<code>apply_settings()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i>	<code>apply_settings()</code> <i>lablib.devices.interface.camera.IROICamera</i>

- method*), 1011
- `apply_settings()` (*py-lablib.devices.interface.stage.IMultiAxisStage method*), 1021
- `apply_settings()` (*py-lablib.devices.interface.stage.IStage method*), 1020
- `apply_settings()` (*py-lablib.devices.Keithley.multimeter.Keithley2110 method*), 668
- `apply_settings()` (*pylablib.devices.KJL.base.KJL300 method*), 664
- `apply_settings()` (*py-lablib.devices.Lakeshore.base.Lakeshore218 method*), 674
- `apply_settings()` (*py-lablib.devices.Lakeshore.base.Lakeshore370 method*), 679
- `apply_settings()` (*py-lablib.devices.LaserQuantum.base.Finesse method*), 684
- `apply_settings()` (*py-lablib.devices.Leybold.base.GenericITR method*), 686
- `apply_settings()` (*py-lablib.devices.Leybold.base.ITR90 method*), 687
- `apply_settings()` (*py-lablib.devices.LighthousePhotonics.base.SproutG method*), 691
- `apply_settings()` (*py-lablib.devices.Lumel.base.LumelRE72Controller method*), 693
- `apply_settings()` (*py-lablib.devices.M2.base.ICEBlocDevice method*), 697
- `apply_settings()` (*pylablib.devices.M2.emm.EMM method*), 699
- `apply_settings()` (*pylablib.devices.M2.solstis.Solstis method*), 706
- `apply_settings()` (*py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method*), 710
- `apply_settings()` (*py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method*), 716
- `apply_settings()` (*py-lablib.devices.Newport.picomotor.Picomotor8742 method*), 738
- `apply_settings()` (*pylablib.devices.NI.daq.NIDAQ method*), 724
- `apply_settings()` (*py-lablib.devices.NKT.interbus.GenericInterbusDevice method*), 726
- `apply_settings()` (*py-lablib.devices.NKT.interbus.GenericInterbusModule method*), 728
- `apply_settings()` (*py-lablib.devices.NKT.interbus.IInterbusModule method*), 727
- `apply_settings()` (*py-lablib.devices.NKT.interbus.InterbusSystem method*), 733
- `apply_settings()` (*py-lablib.devices.NKT.interbus.SuperKExtremeInterbusModule method*), 729
- `apply_settings()` (*py-lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule method*), 730
- `apply_settings()` (*py-lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule method*), 731
- `apply_settings()` (*py-lablib.devices.NKT.interbus.SuperKSelectInterbusModule method*), 732
- `apply_settings()` (*py-lablib.devices.Omron.base.OmronE5xCController method*), 747
- `apply_settings()` (*py-lablib.devices.Ophir.base.OphirDevice method*), 749
- `apply_settings()` (*py-lablib.devices.Ophir.base.VegaPowerMeter method*), 753
- `apply_settings()` (*py-lablib.devices.OZOptics.base.DD100 method*), 743
- `apply_settings()` (*py-lablib.devices.OZOptics.base.EPC04 method*), 745
- `apply_settings()` (*py-lablib.devices.OZOptics.base.OZOpticsDevice method*), 740
- `apply_settings()` (*py-lablib.devices.OZOptics.base.TF100 method*), 742
- `apply_settings()` (*py-lablib.devices.PCO.SC2.PCOSC2Camera method*), 759
- `apply_settings()` (*py-lablib.devices.Pfeiffer.base.DPG202 method*), 768
- `apply_settings()` (*py-lablib.devices.Pfeiffer.base.TPG260 method*), 766
- `apply_settings()` (*py-lablib.devices.Photometrics.pvcam.PvcamCamera method*), 775



<code>apply_settings()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 784	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.elliptec.ElliptecMotor</i> <i>method</i> ), 914	(py-
<code>apply_settings()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlipper</i> <i>method</i> ), 806	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.BasicKinesisDevice</i> <i>method</i> ), 918	(py-
<code>apply_settings()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</i> <i>method</i> ), 788	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisDevice</i> <i>method</i> ), 922	(py-
<code>apply_settings()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 798	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> <i>method</i> ), 932	(py-
<code>apply_settings()</code> <i>lablib.devices.PhysikInstrumente.base.GenericPIController</i> <i>method</i> ), 815	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoController</i> <i>method</i> ), 939	(py-
<code>apply_settings()</code> <i>lablib.devices.PhysikInstrumente.base.PIE515</i> <i>method</i> ), 821	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</i> <i>method</i> ), 936	(py-
<code>apply_settings()</code> <i>lablib.devices.PhysikInstrumente.base.PIE516</i> <i>method</i> ), 817	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</i> <i>method</i> ), 943	(py-
<code>apply_settings()</code> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 830	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.kinesis.MFF</i> <i>method</i> ), 925	(py-
<code>apply_settings()</code> <i>lablib.devices.Rigol.power_supply.DP1116A</i> <i>method</i> ), 835	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.misc.GenericPM</i> <i>method</i> ), 947	(py-
<code>apply_settings()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 849	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.misc.PM160</i> <i>method</i> ), 950	(py-
<code>apply_settings()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method</i> ), 844	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.serial.FW</i> <i>method</i> ), 958	(py-
<code>apply_settings()</code> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method</i> ), 861	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.serial.FWv1</i> <i>method</i> ), 962	(py-
<code>apply_settings()</code> <i>lablib.devices.SmarAct.MCS2.MCS2</i> <i>method</i> ), 872	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.serial.MDT69xA</i> <i>method</i> ), 965	(py-
<code>apply_settings()</code> <i>lablib.devices.SmarAct.scu3d.SCU3D</i> <i>method</i> ), 875	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.serial.ThorlabsSerialInterface</i> <i>method</i> ), 954	(py-
<code>apply_settings()</code> <i>lablib.devices.Standa.base.Standa8SMC</i> <i>method</i> ), 879	(py- <code>apply_settings()</code> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 907	(py-
<code>apply_settings()</code> <i>lablib.devices.Tektronix.base.DPO2000</i> <i>method</i> ), 895	(py- <code>apply_settings()</code> <i>lablib.devices.Toptica.ibeam.TopticaIBeam</i> <i>method</i> ), 970	(py-
<code>apply_settings()</code> <i>lablib.devices.Tektronix.base.ITektronixScope</i> <i>method</i> ), 885	(py- <code>apply_settings()</code> <i>lablib.devices.Trinamic.base.TMCM1110</i> <i>method</i> ), 975	(py-
<code>apply_settings()</code> <i>lablib.devices.Tektronix.base.TDS2000</i> <i>method</i> ), 888	(py- <code>apply_settings()</code> <i>lablib.devices.Trinamic.base.TMCMx110</i> <i>method</i> ), 976	(py-

`apply_settings()` (`pylablib.devices.uc480.uc480.UC480Camera` method), 1028

`apply_settings()` (`pylablib.devices.Voltcraft.multimeter.VC7055` method), 981

`apply_settings()` (`pylablib.devices.Voltcraft.multimeter.VC880` method), 985

`apply_settings()` (`pylablib.devices.Windows.joystick.Joystick` method), 988

`apply_window()` (in module `pylablib.core.dataproc.fourier`), 144

`ArcusBackendError`, 550

`ArcusError`, 550

`ArduinoBackendError`, 564

`ArduinoError`, 563

`area()` (`pylablib.core.dataproc.image.ROI` method), 148

`arg_value()` (`pylablib.core.utils.functions.FunctionSignature` method), 421

`args` (`pylablib.core.devio.base.DeviceError` attribute), 170

`args` (`pylablib.core.devio.comm_backend.DeviceBackendError` attribute), 170

`args` (`pylablib.core.devio.comm_backend.DeviceFT232Error` attribute), 178

`args` (`pylablib.core.devio.comm_backend.DeviceHIDError` attribute), 186

`args` (`pylablib.core.devio.comm_backend.DeviceNetworkError` attribute), 181

`args` (`pylablib.core.devio.comm_backend.DeviceRecordedError` attribute), 189

`args` (`pylablib.core.devio.comm_backend.DeviceSerialError` attribute), 175

`args` (`pylablib.core.devio.comm_backend.DeviceUSBError` attribute), 183

`args` (`pylablib.core.devio.comm_backend.DeviceVisaError` attribute), 172

`args` (`pylablib.core.devio.hid_base.HIDError` attribute), 196

`args` (`pylablib.core.devio.hid_base.HIDLibError` attribute), 196

`args` (`pylablib.core.devio.hid_base.HIDTimeoutError` attribute), 196

`args` (`pylablib.core.gui.limiter.LimitError` attribute), 308

`args` (`pylablib.core.gui.value_handling.MissingGUIHandlerError` attribute), 326

`args` (`pylablib.core.gui.value_handling.NoParameterError` attribute), 311

`args` (`pylablib.core.thread.threadprop.DuplicateControllerThreadError` attribute), 369

`args` (`pylablib.core.thread.threadprop.InterruptExceptionStop` attribute), 370

`args` (`pylablib.core.thread.threadprop.NoControllerThreadError` attribute), 369

`args` (`pylablib.core.thread.threadprop.NoMessageThreadError` attribute), 370

`args` (`pylablib.core.thread.threadprop.SkippedCallError` attribute), 370

`args` (`pylablib.core.thread.threadprop.ThreadError` attribute), 368

`args` (`pylablib.core.thread.threadprop.TimeoutThreadError` attribute), 369

`args` (`pylablib.core.utils.net.SocketError` attribute), 440

`args` (`pylablib.core.utils.net.SocketTimeout` attribute), 440

`args` (`pylablib.devices.Agilent.base.AgilentBackendError` attribute), 505

`args` (`pylablib.devices.Agilent.base.AgilentError` attribute), 505

`args` (`pylablib.devices.AlliedVision.Bonito.BonitoError` attribute), 507

`args` (`pylablib.devices.Andor.base.AndorError` attribute), 549

`args` (`pylablib.devices.Andor.base.AndorFrameTransferError` attribute), 550

`args` (`pylablib.devices.Andor.base.AndorNotSupportedError` attribute), 550

`args` (`pylablib.devices.Andor.base.AndorTimeoutError` attribute), 549

`args` (`pylablib.devices.Arcus.base.ArcusBackendError` attribute), 551

`args` (`pylablib.devices.Arcus.base.ArcusError` attribute), 550

`args` (`pylablib.devices.Arduino.base.ArduinoBackendError` attribute), 564

`args` (`pylablib.devices.Arduino.base.ArduinoError` attribute), 563

`args` (`pylablib.devices.Attocube.base.AttocubeBackendError` attribute), 574

`args` (`pylablib.devices.Attocube.base.AttocubeError` attribute), 574

`args` (`pylablib.devices.AWG.generic.GenericAWGBackendError` attribute), 455

`args` (`pylablib.devices.AWG.generic.GenericAWGError` attribute), 455

`args` (`pylablib.devices.BitFlow.BitFlow.BitFlowError` attribute), 584

`args` (`pylablib.devices.BitFlow.BitFlow.BitFlowTimeoutError` attribute), 585

`args` (`pylablib.devices.Conrad.base.ConradBackendError` attribute), 597

`args` (`pylablib.devices.Conrad.base.ConradError` attribute), 597

`args` (`pylablib.devices.Cryocon.base.CryoconBackendError` attribute), 597

- attribute), 600
- args (pylablib.devices.Cryocon.base.CryoconError attribute), 599
- args (pylablib.devices.Cryomagnetics.base.CryomagneticsBackendError attribute), 604
- args (pylablib.devices.Cryomagnetics.base.CryomagneticsError attribute), 604
- args (pylablib.devices.ElektroAutomatik.base.ElektroAutomatikBackendError attribute), 622
- args (pylablib.devices.ElektroAutomatik.base.ElektroAutomatikError attribute), 622
- args (pylablib.devices.Hubner.base.HubnerBackendError attribute), 633
- args (pylablib.devices.Hubner.base.HubnerError attribute), 633
- args (pylablib.devices.interface.camera.DefaultFrameTransferError attribute), 989
- args (pylablib.devices.Keithley.base.GenericKeithleyBackendError attribute), 665
- args (pylablib.devices.Keithley.base.GenericKeithleyError attribute), 665
- args (pylablib.devices.KJL.base.KJLBackendError attribute), 663
- args (pylablib.devices.KJL.base.KJLError attribute), 663
- args (pylablib.devices.Lakeshore.base.LakeshoreBackendError attribute), 671
- args (pylablib.devices.Lakeshore.base.LakeshoreError attribute), 671
- args (pylablib.devices.LaserQuantum.base.LaserQuantumBackendError attribute), 682
- args (pylablib.devices.LaserQuantum.base.LaserQuantumError attribute), 682
- args (pylablib.devices.Leybold.base.LeyboldBackendError attribute), 685
- args (pylablib.devices.Leybold.base.LeyboldError attribute), 685
- args (pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsBackendError attribute), 689
- args (pylablib.devices.LighthousePhotonics.base.LighthousePhotonicsError attribute), 689
- args (pylablib.devices.M2.base.M2CommunicationError attribute), 695
- args (pylablib.devices.M2.base.M2Error attribute), 695
- args (pylablib.devices.M2.base.M2ParseError attribute), 695
- args (pylablib.devices.Mightex.base.MightexError attribute), 714
- args (pylablib.devices.Mightex.base.MightexTimeoutError attribute), 714
- args (pylablib.devices.Modbus.modbus.ModbusBackendError attribute), 715
- args (pylablib.devices.Modbus.modbus.ModbusError attribute), 714
- args (pylablib.devices.Newport.base.NewportBackendError attribute), 735
- args (pylablib.devices.Newport.base.NewportError attribute), 735
- args (pylablib.devices.NI.daq.NIDAQmxError attribute), 717
- args (pylablib.devices.NI.daq.NIError attribute), 717
- args (pylablib.devices.NKT.interbus.InterbusBackendError attribute), 725
- args (pylablib.devices.NKT.interbus.InterbusError attribute), 725
- args (pylablib.devices.Ophir.base.OphirBackendError attribute), 749
- args (pylablib.devices.Ophir.base.OphirError attribute), 749
- args (pylablib.devices.OZOptics.base.OZOpticsBackendError attribute), 740
- args (pylablib.devices.OZOptics.base.OZOpticsError attribute), 739
- args (pylablib.devices.Pfeiffer.base.PfeifferBackendError attribute), 764
- args (pylablib.devices.Pfeiffer.base.PfeifferError attribute), 763
- args (pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteBackendError attribute), 814
- args (pylablib.devices.PhysikInstrumente.base.PhysikInstrumenteError attribute), 814
- args (pylablib.devices.Rigol.base.GenericRigolBackendError attribute), 834
- args (pylablib.devices.Rigol.base.GenericRigolError attribute), 834
- args (pylablib.devices.Sirah.base.GenericSirahBackendError attribute), 864
- args (pylablib.devices.Sirah.base.GenericSirahError attribute), 864
- args (pylablib.devices.Sirah.tuner.FrequencyReadSirahError attribute), 864
- args (pylablib.devices.SmarAct.base.SmarActError attribute), 873
- args (pylablib.devices.Standa.base.StandaBackendError attribute), 876
- args (pylablib.devices.Standa.base.StandaError attribute), 876
- args (pylablib.devices.Tektronix.base.TektronixBackendError attribute), 881
- args (pylablib.devices.Tektronix.base.TektronixError attribute), 880
- args (pylablib.devices.Thorlabs.base.ThorlabsBackendError attribute), 911
- args (pylablib.devices.Thorlabs.base.ThorlabsError attribute), 911
- args (pylablib.devices.Thorlabs.base.ThorlabsTimeoutError attribute), 911
- args (pylablib.devices.Toptica.base.TopticaBackendError attribute), 911

attribute), 968  
 args (pylablib.devices.Toptica.base.TopticaError attribute), 968  
 args (pylablib.devices.Trinamic.base.TrinamicBackendError attribute), 971  
 args (pylablib.devices.Trinamic.base.TrinamicError attribute), 971  
 args (pylablib.devices.Trinamic.base.TrinamicTimeoutError attribute), 971  
 args (pylablib.devices.Voltcraft.base.GenericVoltcraftBackendError attribute), 980  
 args (pylablib.devices.Voltcraft.base.GenericVoltcraftError attribute), 980  
 args (pylablib.devices.Voltcraft.mmultimeter.VC880ParseError attribute), 984  
 Array1DWrapper (class in pylablib.core.dataproc.table\_wrap), 153  
 Array1DWrapper.Accessor (class in pylablib.core.dataproc.table\_wrap), 154  
 Array2DWrapper (class in pylablib.core.dataproc.table\_wrap), 157  
 Array2DWrapper.ColumnAccessor (class in pylablib.core.dataproc.table\_wrap), 157  
 Array2DWrapper.RowAccessor (class in pylablib.core.dataproc.table\_wrap), 157  
 Array2DWrapper.TableAccessor (class in pylablib.core.dataproc.table\_wrap), 158  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.Array1DWrapper method), 154  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.Array2DWrapper method), 158  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper method), 161  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.I1DWrapper method), 153  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.I2DWrapper method), 156  
 array\_replaced() (pylablib.core.dataproc.table\_wrap.Series1DWrapper method), 155  
 article\_no (pylablib.devices.ElektroAutomatik.base.TDDevice attribute), 622  
 as\_addr\_port() (in module pylablib.core.utils.net), 441  
 as\_array() (in module pylablib.core.utils.array\_utils), 371  
 as\_builtin\_bytes() (in module pylablib.core.utils.py3), 446  
 as\_bytes() (in module pylablib.core.utils.py3), 446  
 as\_container() (in module pylablib.core.utils.general), 425  
 as\_datatype() (in module pylablib.core.utils.py3), 446  
 as\_dict() (in module pylablib.core.utils.dictionary), 377  
 as\_dict() (pylablib.core.utils.dictionary.Dictionary method), 382  
 as\_dict() (pylablib.core.utils.dictionary.DictionaryPointer method), 387  
 as\_dict() (pylablib.core.utils.dictionary.FilterTree method), 404  
 as\_dict() (pylablib.core.utils.dictionary.PrefixTree method), 395  
 as\_dictionary() (in module pylablib.core.utils.dictionary), 377  
 as\_dictionary() (pylablib.core.utils.dictionary.Dictionary static method), 377  
 as\_dictionary() (pylablib.core.utils.dictionary.DictionaryPointer static method), 387  
 as\_dictionary() (pylablib.core.utils.dictionary.FilterTree static method), 404  
 as\_dictionary() (pylablib.core.utils.dictionary.PrefixTree static method), 396  
 as\_formatter() (in module pylablib.core.gui.formatter), 307  
 as\_json() (pylablib.core.utils.dictionary.Dictionary method), 383  
 as\_json() (pylablib.core.utils.dictionary.DictionaryPointer method), 387  
 as\_json() (pylablib.core.utils.dictionary.FilterTree method), 404  
 as\_json() (pylablib.core.utils.dictionary.PrefixTree method), 396  
 as\_kwargs() (pylablib.core.utils.functions.FunctionSignature method), 421  
 as\_limiter() (in module pylablib.core.gui.limiter), 308  
 as\_obj\_prop() (in module pylablib.core.utils.functions), 424  
 as\_pandas() (pylablib.core.utils.dictionary.Dictionary method), 383  
 as\_pandas() (pylablib.core.utils.dictionary.DictionaryPointer method), 387  
 as\_pandas() (pylablib.core.utils.dictionary.FilterTree method), 404  
 as\_pandas() (pylablib.core.utils.dictionary.PrefixTree method), 396  
 as\_sequence() (in module pylablib.core.utils.funcargparse), 420  
 as\_simple\_func() (pylablib.core.utils.functions.FunctionSignature method), 421



- `as_str()` (in module `pylablib.core.utils.py3`), 446
- `as_text()` (`pylablib.devices.DCAM.DCAM.DCAMAttribute` method), 614
- `asdict()` (`pylablib.core.utils.dictionary.Dictionary` method), 383
- `asdict()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 387
- `asdict()` (`pylablib.core.utils.dictionary.FilterTree` method), 404
- `asdict()` (`pylablib.core.utils.dictionary.PrefixTree` method), 396
- `ask()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` method), 180
- `ask()` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` method), 188
- `ask()` (`pylablib.core.devio.comm_backend.IDeviceCommBackend` method), 172
- `ask()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` method), 182
- `ask()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` method), 185
- `ask()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` method), 190
- `ask()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` method), 177
- `ask()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` method), 174
- `ask()` (`pylablib.core.devio.SCPIDevice` method), 168
- `ask()` (`pylablib.devices.AWG.generic.GenericAWG` method), 459
- `ask()` (`pylablib.devices.AWG.specific.Agilent33220A` method), 468
- `ask()` (`pylablib.devices.AWG.specific.Agilent33500` method), 462
- `ask()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 480
- `ask()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 474
- `ask()` (`pylablib.devices.AWG.specific.RigolDG1000` method), 499
- `ask()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 487
- `ask()` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 493
- `ask()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 601
- `ask()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 606
- `ask()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 609
- `ask()` (`pylablib.devices.Keithley.multimeter.Keithley2110` method), 668
- `ask()` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 674
- `ask()` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 679
- `ask()` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 821
- `ask()` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 835
- `ask()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 857
- `ask()` (`pylablib.devices.Tektronix.base.DPO2000` method), 895
- `ask()` (`pylablib.devices.Tektronix.base.ITektronixScope` method), 885
- `ask()` (`pylablib.devices.Tektronix.base.TDS2000` method), 888
- `ask()` (`pylablib.devices.Thorlabs.misc.GenericPM` method), 947
- `ask()` (`pylablib.devices.Thorlabs.misc.PM160` method), 950
- `ask()` (`pylablib.devices.Thorlabs.serial.FW` method), 957
- `ask()` (`pylablib.devices.Thorlabs.serial.FWv1` method), 961
- `ask()` (`pylablib.devices.Thorlabs.serial.MDT69xA` method), 965
- `ask()` (`pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface` method), 955
- `ask()` (`pylablib.devices.Voltcraft.multimeter.VC7055` method), 981
- `atm_adj` (`pylablib.devices.Leybold.base.TITR90Status` attribute), 687
- `AttocubeBackendError`, 574
- `AttocubeError`, 574
- `attr` (`pylablib.core.utils.observer_pool.ObserverPool.Observer` attribute), 445
- `attr_url` (`pylablib.devices.IMAQdx.IMAQdx.TCameraInfo` attribute), 648
- `AttrObjectCall` (class in `pylablib.core.utils.functions`), 423
- `AttrObjectProperty` (class in `pylablib.core.utils.functions`), 424
- `au1()` (in module `pylablib.core.utils.nbtools`), 439
- `au2()` (in module `pylablib.core.utils.nbtools`), 439
- `au4()` (in module `pylablib.core.utils.nbtools`), 439
- `au8()` (in module `pylablib.core.utils.nbtools`), 439
- `autodetect_backend()` (in module `pylablib.core.devio.comm_backend`), 191
- `autodetect_motors()` (`pylablib.devices.Newport.picomotor.Picomotor8742` method), 737
- `autoloop` (`pylablib.devices.NI.daq.TVoltageOutputClockParameters` attribute), 718
- `autorange` (`pylablib.devices.Lakeshore.base.TLakeshore370RangeSettings` attribute), 677

[autorng \(pylablib.devices.Keithley.multimeter.TGenericFunctionGenerator attribute\), 666](#)  
[available \(pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute\), 576](#)  
[available \(pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute\), 770](#)  
[available\\_samples\(\) \(pylablib.devices.NI.daq.NIDAQ method\), 720](#)  
[average\\_interpolate\\_1D\(\) \(in module py-lablib.core.dataproc.interpolate\), 150](#)  
[avg \(pylablib.devices.Sirah.Matisse.TPiezoetFeedbackParameters attribute\), 855](#)  
[avg \(pylablib.devices.Sirah.Matisse.TThinCtlParameters attribute\), 855](#)

**B**

[backend\\_error\(\) \(in module py-lablib.core.devio.comm\\_backend\), 192](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.FT232RLBackend attribute\), 178](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.HIDDeviceBackend attribute\), 187](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.IDeviceCommBackend attribute\), 171](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.NetworkDeviceBackend attribute\), 181](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.PyUSBDeviceBackend attribute\), 184](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.RecorderDeviceBackend attribute\), 189](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.SerialDeviceBackend attribute\), 176](#)  
[BackendError \(pylablib.core.devio.comm\\_backend.VisaDeviceBackend attribute\), 173](#)  
[BackendError \(pylablib.core.devio.SCPI.SCPIDevice attribute\), 166](#)  
[BackendError \(pylablib.devices.AWG.generic.GenericAWG attribute\), 458](#)  
[BackendError \(pylablib.devices.AWG.specific.Agilent33229A attribute\), 468](#)  
[BackendError \(pylablib.devices.AWG.specific.Agilent3350B attribute\), 462](#)  
[BackendError \(pylablib.devices.AWG.specific.InstekAFG2600 attribute\), 480](#)  
[BackendError \(pylablib.devices.AWG.specific.InstekAFG225 attribute\), 474](#)  
[BackendError \(pylablib.devices.AWG.specific.RigolDG1000 attribute\), 499](#)  
[BackendError \(pylablib.devices.AWG.specific.RSInstekAF6200 attribute\), 486](#)  
[BackendError \(pylablib.devices.AWG.specific.TektronixAF601 attribute\), 493](#)  
[BackendError \(pylablib.devices.Cryocon.base.CryoconInterface attribute\), 601](#)

[BackendError \(pylablib.devices.Cryomagnetics.base.LM500 attribute\), 605](#)  
[BackendError \(pylablib.devices.Cryomagnetics.base.LM510 attribute\), 608](#)  
[BackendError \(pylablib.devices.Keithley.multimeter.Keithley2110 attribute\), 668](#)  
[BackendError \(pylablib.devices.Lakeshore.base.Lakeshore218 attribute\), 674](#)  
[BackendError \(pylablib.devices.Lakeshore.base.Lakeshore370 attribute\), 679](#)  
[BackendError \(pylablib.devices.M2.base.ICEBlocDevice attribute\), 696](#)  
[BackendError \(pylablib.devices.M2.emm.EMM attribute\), 699](#)  
[BackendError \(pylablib.devices.M2.solstis.Solstis attribute\), 705](#)  
[BackendError \(pylablib.devices.PhysikInstrumente.base.PIE515 attribute\), 821](#)  
[BackendError \(pylablib.devices.Rigol.power\\_supply.DP1116A attribute\), 835](#)  
[BackendError \(pylablib.devices.Sirah.Matisse.SirahMatisse attribute\), 861](#)  
[BackendError \(pylablib.devices.Tektronix.base.DPO2000 attribute\), 895](#)  
[BackendError \(pylablib.devices.Tektronix.base.ITektronixScope attribute\), 885](#)  
[BackendError \(pylablib.devices.Tektronix.base.TDS2000 attribute\), 888](#)  
[BackendError \(pylablib.devices.Thorlabs.misc.GenericPM attribute\), 947](#)  
[BackendError \(pylablib.devices.Thorlabs.misc.PM160 attribute\), 950](#)  
[BackendError \(pylablib.devices.Thorlabs.serial.FW attribute\), 958](#)  
[BackendError \(pylablib.devices.Thorlabs.serial.FWv1 attribute\), 961](#)  
[BackendError \(pylablib.devices.Thorlabs.serial.MDT69xA attribute\), 965](#)  
[BackendError \(pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface attribute\), 954](#)  
[BackendError \(pylablib.devices.Voltcraft.multimeter.VC7055 attribute\), 981](#)  
[BackendLogger \(class in py-lablib.core.devio.backend\\_logger\), 169](#)  
[backlash\\_distance \(pylablib.devices.Thorlabs.kinesis.TGenMoveParams attribute\), 919](#)  
[Baseline \(class in pylablib.core.dataproc.feature\), 135](#)  
[baseline\\_interpolate \(pylablib.devices.Toptica.ibeam.TTemperatures attribute\), 968](#)  
[BasicKinesisDevice \(class in py-lablib.devices.Thorlabs.kinesis\), 916](#)  
[BasicKinesisDevice.CommData \(class in py-lablib.devices.Thorlabs.kinesis\), 917](#)

- BasicKinesisDevice.CommShort (class in py-lablib.devices.Thorlabs.kinesis), 917
- BaslerPylonAttribute (class in py-lablib.devices.Basler.pylon), 575
- BaslerPylonCamera (class in py-lablib.devices.Basler.pylon), 578
- BaslerPylonCamera.BufferManager (class in py-lablib.devices.Basler.pylon), 579
- BaslerPylonCamera.ScheduleLooper (class in py-lablib.devices.Basler.pylon), 580
- bayer\_interpolate() (in module py-lablib.devices.utils.color), 1031
- bifi\_clear\_errors() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_get\_position() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_get\_range() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_get\_status() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_get\_status\_n() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_home() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_is\_moving() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_move\_to() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_stop() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 857
- bifi\_wait\_move() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
- BinaryTableInputFileFormatter (class in py-lablib.core.fileio.loadfile), 212
- bind() (pylablib.core.dataproc.callable.FunctionCallable method), 132
- bind() (pylablib.core.dataproc.callable.ICallable method), 130
- bind() (pylablib.core.dataproc.callable.JoinedCallable method), 131
- bind() (pylablib.core.dataproc.callable.MethodCallable method), 133
- bind() (pylablib.core.dataproc.callable.MultiplexedCallable method), 131
- bind\_namelist() (py-lablib.core.dataproc.callable.FunctionCallable method), 132
- bind\_namelist() (py-lablib.core.dataproc.callable.ICallable method), 130
- bind\_namelist() (py-lablib.core.dataproc.callable.JoinedCallable method), 131
- bind\_namelist() (py-lablib.core.dataproc.callable.MethodCallable method), 133
- bind\_namelist() (py-lablib.core.dataproc.callable.MultiplexedCallable method), 131
- binning\_average() (in module py-lablib.core.dataproc.filters), 139
- binv() (in module pylablib.core.utils.crc), 372
- bipolar (pylablib.devices.Lakeshore.base.TLakeshore218AnalogSettings attribute), 671
- bipolar (pylablib.devices.Lakeshore.base.TLakeshore370AnalogSettings attribute), 677
- bit\_depth (pylablib.devices.Thorlabs.TLCamera.TSensorInfo attribute), 903
- BitFlowCamera (class in py-lablib.devices.BitFlow.BitFlow), 591
- BitFlowCamera.BufferManager (class in py-lablib.devices.BitFlow.BitFlow), 591
- BitFlowError, 584
- BitFlowFrameGrabber (class in py-lablib.devices.BitFlow.BitFlow), 585
- BitFlowFrameGrabber.BufferManager (class in py-lablib.devices.BitFlow.BitFlow), 586
- BitFlowTimeoutError, 584
- bits2int() (in module pylablib.core.utils.strpack), 453
- bits\_freq (pylablib.devices.Thorlabs.elliptec.TMotorInfo attribute), 912
- blaze\_wavelength (py-lablib.devices.Andor.Shamrock.TGratingInfo attribute), 545
- blink() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 918
- blink() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 922
- blink() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 932
- blink() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939
- blink() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 936
- blink() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943
- blink() (pylablib.devices.Thorlabs.kinesis.MFF method), 925
- blocking\_control\_signals() (py-lablib.core.thread.controller.QTaskThread method), 357

blocking\_control\_signals() (pylablib.core.thread.controller.QThreadController method), 334  
 boards\_rev (pylablib.devices.Agilent.pressure.TXGS600DeviceInfo attribute), 505  
 BonitoError, 507  
 BonitoIMAQCamera (class in pylablib.devices.AlliedVision.Bonito), 513  
 BonitoStatusLineChecker (class in pylablib.devices.AlliedVision.Bonito), 522  
 branch\_copy() (pylablib.core.utils.dictionary.Dictionary method), 382  
 branch\_copy() (pylablib.core.utils.dictionary.DictionaryPointer method), 388  
 branch\_copy() (pylablib.core.utils.dictionary.FilterTree method), 404  
 branch\_copy() (pylablib.core.utils.dictionary.PrefixTree method), 396  
 branch\_pointer() (pylablib.core.utils.dictionary.Dictionary method), 383  
 branch\_pointer() (pylablib.core.utils.dictionary.DictionaryPointer method), 386  
 branch\_pointer() (pylablib.core.utils.dictionary.FilterTree method), 404  
 branch\_pointer() (pylablib.core.utils.dictionary.PrefixTree method), 396  
 buffconv() (in module pylablib.core.utils.ctypes\_wrap), 374  
 buffer\_size (pylablib.devices.interface.camera.TFramesSource attribute), 989  
 buffprep() (in module pylablib.core.utils.ctypes\_wrap), 374  
 build\_call() (pylablib.core.thread.callsync.QDirectCallScheduler method), 334  
 build\_call() (pylablib.core.thread.callsync.QMulticastThreadCallScheduler method), 340  
 build\_call() (pylablib.core.thread.callsync.QMultiQueueScheduler method), 339  
 build\_call() (pylablib.core.thread.callsync.QQueueLengthLimitScheduler method), 336  
 build\_call() (pylablib.core.thread.callsync.QQueueScheduler method), 335  
 build\_call() (pylablib.core.thread.callsync.QQueueSizeLimitScheduler method), 338  
 build\_call() (pylablib.core.thread.callsync.QScheduler method), 333  
 build\_call() (pylablib.core.thread.callsync.QThreadCallScheduler method), 339  
 build\_call\_info() (pylablib.core.thread.callsync.QDirectCallScheduler method), 334  
 build\_call\_info() (pylablib.core.thread.callsync.QMulticastThreadCallScheduler method), 341  
 build\_call\_info() (pylablib.core.thread.callsync.QQueueLengthLimitScheduler method), 337  
 build\_call\_info() (pylablib.core.thread.callsync.QQueueScheduler method), 336  
 build\_call\_info() (pylablib.core.thread.callsync.QQueueSizeLimitScheduler method), 338  
 build\_call\_info() (pylablib.core.thread.callsync.QScheduler method), 333  
 build\_call\_info() (pylablib.core.thread.callsync.QThreadCallScheduler method), 340  
 build\_children\_tree() (in module pylablib.core.gui.value\_handling), 311  
 build\_file\_format() (in module pylablib.core.fileio.loadfile), 212  
 bus (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 648  
 bus\_type (pylablib.devices.IMAQdx.IMAQdx.TDeviceInfo attribute), 650  
 ButtonSelector (class in pylablib.core.gui.widgets.button\_selector), 232  
 byref() (pylablib.core.utils.ctypes\_wrap.CFunctionWrapper method), 373  
 bytes2int() (in module pylablib.core.utils.strpack), 453

## C

c\_array() (in module pylablib.core.dataproc.utils), 165  
 c\_array() (in module pylablib.core.utils.nbtools), 439  
 call\_scheduler() (pylablib.core.thread.controller.QTaskThread attribute), 350  
 cacheable (pylablib.core.utils.observer\_pool.ObserverPool.Observer attribute), 445  
 call\_scheduler() (pylablib.core.thread.controller.QTaskThread attribute), 350  
 call\_scheduler() (pylablib.core.thread.controller.QTaskThread attribute), 350  
 call\_scheduler() (pylablib.core.thread.controller.QTaskThread attribute), 350  
 call\_scheduler() (pylablib.devices.LaserQuantum.base.TDeviceInfo attribute), 682  
 calc\_table() (in module pylablib.core.utils.crc), 372  
 calibrate() (pylablib.devices.HighFinesse.wlm.WLM method), 628  
 calibrate() (pylablib.devices.Sirah.tuner.MatisseTuner method), 866



`calibrate()` (`pylablib.devices.SmarAct.MCS2.MCS2` method), 872  
`calibration` (`pylablib.devices.Thorlabs.misc.TPMSensorInfo` attribute), 945  
`call_added()` (`pylablib.core.thread.callsync.QQueueLengthLimitScheduler` method), 336  
`call_added()` (`pylablib.core.thread.callsync.QQueueScheduler` method), 335  
`call_added()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` method), 338  
`call_command()` (`pylablib.core.thread.controller.QTaskThread` method), 355  
`call_command()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Kropid` method), 536  
`call_command()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Kropid` method), 537  
`call_command()` (`pylablib.devices.Basler.pylon.BaslerPylonAttribute` method), 577  
`call_command()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera` method), 578  
`call_command()` (`pylablib.devices.PhotonFocus.PhotonFocusPylonCamera` method), 782  
`call_command()` (`pylablib.devices.PhotonFocus.PhotonFocusPylonCamera` method), 781  
`call_command()` (`pylablib.devices.PhotonFocus.PhotonFocusPylonCamera` method), 806  
`call_command()` (`pylablib.devices.PhotonFocus.PhotonFocusPylonCamera` method), 788  
`call_command()` (`pylablib.devices.PhotonFocus.PhotonFocusPylonCamera` method), 798  
`call_command_direct()` (`pylablib.core.thread.controller.QTaskThread` method), 355  
`call_cut_args()` (in module `pylablib.core.utils.functions`), 422  
`call_in_gui_thread()` (in module `pylablib.core.thread.controller`), 341  
`call_in_thread()` (in module `pylablib.core.thread.controller`), 341  
`call_in_thread_callback()` (`pylablib.core.thread.controller.QTaskThread` method), 357  
`call_in_thread_callback()` (`pylablib.core.thread.controller.QThreadController` method), 349  
`call_in_thread_commsync()` (`pylablib.core.thread.controller.QTaskThread` method), 356  
`call_in_thread_sync()` (`pylablib.core.thread.controller.QTaskThread` method), 357  
`call_in_thread_sync()` (`pylablib.core.thread.controller.QThreadController` method), 349  
`call_limit()` (in module `pylablib.core.utils.general`), 429  
`call_on_exception` (`pylablib.core.thread.callsync.QScheduledCall.Callback` attribute), 332  
`call_on_unschedule` (`pylablib.core.thread.callsync.QScheduledCall.Callback` attribute), 332  
`call_popped()` (`pylablib.core.thread.callsync.QQueueScheduler` method), 335  
`call_popped()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` method), 338  
`call_read()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Kropid` method), 536  
`call_thread_method()` (`pylablib.core.thread.controller.QTaskThread` method), 357  
`call_thread_method()` (`pylablib.core.thread.controller.QThreadController` method), 347  
`call_time_pylon_camera` (`pylablib.core.thread.callsync.TDefaultCallInfo` attribute), 333  
`call_time_pylon_camera` (`pylablib.core.thread.callsync.TDefaultCallInfo` attribute), 445  
`can_change()` (`pylablib.core.thread.utils.ReadChangeLock` method), 371  
`can_read()` (`pylablib.core.thread.utils.ReadChangeLock` method), 371  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueLengthLimitScheduler` method), 336  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueScheduler` method), 335  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` method), 338  
`can_set_online` (`pylablib.devices.PrincetonInstruments.picam.PicamAttribute` attribute), 826  
`camera_model` (`pylablib.devices.Andor.AndorSDK3.TDeviceInfo` attribute), 536  
`camera_name` (`pylablib.devices.Andor.AndorSDK3.TDeviceInfo` attribute), 536  
`camera_type` (`pylablib.devices.uc480.uc480.TDeviceInfo` attribute), 1023  
`camera_version` (`pylablib.devices.DCAM.DCAM.TDeviceInfo` attribute), 615  
`CameraFileEditor` (class in `pylablib.devices.BitFlow.BitFlow`), 596  
`camerastamp` (`pylablib.devices.DCAM.DCAM.TFrameInfo` attribute), 615  
`can_change()` (`pylablib.core.thread.utils.ReadChangeLock` method), 371  
`can_read()` (`pylablib.core.thread.utils.ReadChangeLock` method), 371  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueLengthLimitScheduler` method), 336  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueScheduler` method), 335  
`can_schedule()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` method), 338  
`can_set_online` (`pylablib.devices.PrincetonInstruments.picam.PicamAttribute` attribute), 826

`can_set_value()` (py-lablib.core.thread.controller.QTaskThread  
 lablib.core.gui.value\_handling.CheckboxValueHandler method), 320  
`can_set_value()` (py-lablib.core.thread.controller.QTaskThread  
 lablib.core.gui.value\_handling.ComboBoxValueHandler method), 323  
`can_set_value()` (py-lablib.core.gui.widgets.container.IQWidgetContainer  
 lablib.core.gui.value\_handling.IBoolValueHandler method), 243  
`can_set_value()` (py-lablib.core.gui.widgets.container.QDialogContainer  
 lablib.core.gui.value\_handling.ISingleValueHandler method), 257  
`can_set_value()` (py-lablib.core.gui.widgets.container.QFrameContainer  
 lablib.core.gui.value\_handling.IValueHandler method), 252  
`can_set_value()` (py-lablib.core.gui.widgets.container.QGroupBoxContainer  
 lablib.core.gui.value\_handling.LabelValueHandler method), 261  
`can_set_value()` (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContain  
 lablib.core.gui.value\_handling.LineEditValueHandler method), 266  
`can_set_value()` (py-lablib.core.gui.widgets.container.QWidgetContainer  
 lablib.core.gui.value\_handling.ProgressBarValueHandler method), 247  
`can_set_value()` (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget  
 lablib.core.gui.value\_handling.PropertyValueHandler method), 280  
`can_set_value()` (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget  
 lablib.core.gui.value\_handling.PushButtonValueHandler method), 282  
`can_set_value()` (py-lablib.core.gui.widgets.param\_table.ParamTable  
 lablib.core.gui.value\_handling.StandardValueHandler method), 293  
`can_set_value()` (py-lablib.core.gui.widgets.param\_table.StatusTable  
 lablib.core.gui.value\_handling.ToolButtonValueHandler method), 303  
`can_set_value()` (py-lablib.core.thread.callsync.QQueueLengthLimitScheduler  
 lablib.core.gui.value\_handling.VirtualValueHandler method), 336  
`capabilities` (pylablib.devices.Ophir.base.THeadInfo  
 attribute), 750  
`case_sensitive_path()` (in module py-lablib.core.utils.files), 413  
`cast()` (pylablib.core.gui.limiter.NumberLimit method), 308  
`category` (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo  
 attribute), 839  
`center()` (pylablib.core.dataproc.image.ROI method), 148  
`CFunctionWrapper` (class in py-lablib.core.utils.ctypes\_wrap), 372  
`change_addr()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor  
 method), 913  
`change_batch_job_parameters()` (py-lablib.core.thread.callsync.QQueueSizeLimitScheduler  
 method), 338  
`change_period()` (py-lablib.core.thread.controller.QTaskThread.Job  
 method), 352  
`change_period()` (pylablib.core.utils.general.Timer  
 method), 430  
`changed_from` (pylablib.core.utils.dictionary.DictionaryDiff  
 attribute), 385  
`changed_to` (pylablib.core.utils.dictionary.DictionaryDiff  
 attribute), 385  
`changing()` (pylablib.core.thread.utils.ReadChangeLock  
 method), 371  
`channel` (pylablib.devices.Lakeshore.base.TLakeshore218AnalogSettings  
 attribute), 671

channel (pylablib.devices.Lakeshore.base.TLakeshore370AnalogSettings attribute), 677

channel (pylablib.devices.Pfeiffer.base.TTPG260SwitchSettings attribute), 764

characters\_written (pylablib.core.thread.threadprop.TimeoutThreadError attribute), 369

characters\_written (pylablib.core.utils.net.SocketError attribute), 440

characters\_written (pylablib.core.utils.net.SocketTimeout attribute), 440

check\_alias() (pylablib.core.devio.interface.EnumParameterClass method), 200

check\_alias() (pylablib.core.devio.interface.FunctionParameterClass method), 201

check\_alias() (pylablib.core.devio.interface.ICheckingParameterClass method), 198

check\_alias() (pylablib.core.devio.interface.IEnumParameterClass method), 199

check\_alias() (pylablib.core.devio.interface.RangeParameterClass method), 198

check\_background\_comm() (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 917

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 922

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 932

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 936

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943

check\_background\_comm() (pylablib.devices.Thorlabs.kinesis.MFF method), 925

check\_fast\_scan\_start\_report() (pylablib.devices.M2.solstis.Solstis method), 705

check\_fine\_tuning\_report() (pylablib.devices.M2.emm.EMM method), 698

check\_fine\_tuning\_report() (pylablib.devices.M2.solstis.Solstis method),

check\_grabber\_association() (in module py-lablib.devices.AlliedVision.Bonito), 521

check\_grabber\_association() (in module py-lablib.devices.PhotonFocus.PhotonFocus), 812

check\_indices() (pylablib.devices.AlliedVision.Bonito.BonitoStatusLineChecker method), 522

check\_indices() (pylablib.devices.interface.camera.StatusLineChecker method), 1019

check\_indices() (pylablib.devices.PCO.SC2.StatusLineChecker method), 763

check\_indices() (pylablib.devices.PhotonFocus.PhotonFocus.StatusLineChecker method), 813

check\_limit() (pylablib.devices.Attocube.anc350.ANC350 method), 571

check\_limit\_error() (pylablib.devices.Arcus.performax.Performax2EXStage method), 557

check\_limit\_error() (pylablib.devices.Arcus.performax.Performax4EXStage method), 554

check\_limit\_error() (pylablib.devices.Arcus.performax.PerformaxDMXJSAStage method), 561

check\_messages() (pylablib.core.thread.controller.QTaskThread method), 357

check\_messages() (pylablib.core.thread.controller.QThreadController method), 343

check\_parameter\_range() (in module py-lablib.core.utils.funcargparse), 419

check\_report() (pylablib.devices.M2.base.ICEBlocDevice method), 697

check\_report() (pylablib.devices.M2.emm.EMM method), 699

check\_report() (pylablib.devices.M2.solstis.Solstis method), 706

check\_tell() (pylablib.devices.Attocube.anc350.ANC350 method), 570

check\_terascan\_start\_report() (pylablib.devices.M2.emm.EMM method), 699

check\_terascan\_start\_report() (pylablib.devices.M2.solstis.Solstis method), 704

check\_terascan\_update() (pylablib.devices.M2.emm.EMM method), 699

check\_terascan\_update() (pylablib.devices.M2.solstis.Solstis method),

- 704
- `check_value()` (pylablib.core.devio.interface.EnumParameter method), 200
- `check_value()` (pylablib.core.devio.interface.FunctionParameter method), 201
- `check_value()` (pylablib.core.devio.interface.ICheckingParameter method), 198
- `check_value()` (pylablib.core.devio.interface.IEnumParameter method), 199
- `check_value()` (pylablib.core.devio.interface.RangeParameter method), 198
- `CheckboxValueHandler` (class in pylablib.core.gui.value\_handling), 320
- `chip` (pylablib.devices.Photometrics.pvcam.TDDeviceInfo attribute), 771
- `ChunkBufferManager` (class in pylablib.devices.interface.camera), 995
- `ChunksAccumulator` (class in pylablib.core.fileio.parse\_csv), 222
- `class_tuple_to_dict()` (in module pylablib.core.utils.ctypes\_wrap), 376
- `clean_dir()` (in module pylablib.core.utils.files), 414
- `clean_layout()` (in module pylablib.core.gui.utils), 309
- `clean_modes()` (pylablib.devices.BitFlow.BitFlow.CameraFileEditor method), 596
- `cleanup` (pylablib.core.thread.controller.QTaskThread.TBAttribute attribute), 351
- `cleanup()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCameraRingBuffer method), 904
- `clear()` (pylablib.core.gui.widgets.container.IQContainer method), 237
- `clear()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 242
- `clear()` (pylablib.core.gui.widgets.container.QContainer method), 239
- `clear()` (pylablib.core.gui.widgets.container.QDialogContainer method), 257
- `clear()` (pylablib.core.gui.widgets.container.QFrameContainer method), 252
- `clear()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 261
- `clear()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 269
- `clear()` (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainerWidget method), 266
- `clear()` (pylablib.core.gui.widgets.container.QTabContainer method), 272
- `clear()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 247
- `clear()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 281
- `clear()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 282
- `clear()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 292
- `clear()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 303
- `clear()` (pylablib.core.thread.callsync.QDirectCallScheduler method), 334
- `clear()` (pylablib.core.thread.callsync.QMulticastThreadCallScheduler method), 341
- `clear()` (pylablib.core.thread.callsync.QQueueLengthLimitScheduler method), 337
- `clear()` (pylablib.core.thread.callsync.QQueueScheduler method), 335
- `clear()` (pylablib.core.thread.callsync.QQueueSizeLimitScheduler method), 338
- `clear()` (pylablib.core.thread.callsync.QScheduler method), 333
- `clear()` (pylablib.core.thread.callsync.QThreadCallScheduler method), 340
- `clear()` (pylablib.core.thread.controller.QTaskThread.Job method), 352
- `clear_acquisition()` (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 513
- `clear_acquisition()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 509
- `clear_acquisition()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 530
- `clear_acquisition()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 539
- `clear_acquisition()` (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 580
- `clear_acquisition()` (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 591
- `clear_acquisition()` (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 587
- `clear_acquisition()` (pylablib.devices.DCAM.DCAM.DCAMCamera method), 617
- `clear_acquisition()` (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 641
- `clear_acquisition()` (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 637
- `clear_acquisition()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 657
- `clear_acquisition()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 657



method), 652

clear\_acquisition() (py-lablib.devices.interface.camera.IAttributeCamera method), 997

clear\_acquisition() (py-lablib.devices.interface.camera.IBinROICamera method), 1015

clear\_acquisition() (py-lablib.devices.interface.camera.ICamera method), 990

clear\_acquisition() (py-lablib.devices.interface.camera.IExposureCamera method), 1006

clear\_acquisition() (py-lablib.devices.interface.camera.IGrabberAttributeCamera method), 1001

clear\_acquisition() (py-lablib.devices.interface.camera.IROICamera method), 1011

clear\_acquisition() (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 710

clear\_acquisition() (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 758

clear\_acquisition() (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 775

clear\_acquisition() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 784

clear\_acquisition() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 806

clear\_acquisition() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 788

clear\_acquisition() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusQCamera method), 798

clear\_acquisition() (py-lablib.devices.PrincetonInstruments.picam.PicamCamera method), 829

clear\_acquisition() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 849

clear\_acquisition() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 844

clear\_acquisition() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 906

clear\_acquisition() (py-lablib.devices.uc480.uc480.UC480Camera method), 1026

clear\_all\_triggers() (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 514

clear\_all\_triggers() (py-lablib.devices.IMAQ.IMAQ.IMAQCamera method), 641

clear\_all\_triggers() (py-lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 636

clear\_all\_triggers() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 788

clear\_error() (pylablib.devices.Hubner.Cobolt.Cobolt method), 630

clear\_limit\_error() (py-lablib.devices.Arcus.performax.Performax2EXStage method), 557

clear\_limit\_error() (py-lablib.devices.Arcus.performax.Performax4EXStage method), 554

clear\_limit\_error() (py-lablib.devices.Arcus.performax.PerformaxDMXJSASage method), 561

clicked (pylablib.core.gui.widgets.label.EnumLabel attribute), 277

clicked (pylablib.core.gui.widgets.label.NumLabel attribute), 278

clicked (pylablib.core.gui.widgets.label.TextLabel attribute), 277

ClientSocket (class in pylablib.core.utils.net), 441

CLinear2DTransform (class in pylablib.devices.dataproc.ctransform\_fallback), 134

close() (pylablib.core.devio.comm\_backend.FT232DeviceBackend method), 179

close() (pylablib.core.devio.comm\_backend.HIDDeviceBackend method), 187

close() (pylablib.core.devio.comm\_backend.ICommBackendWrapper method), 192

close() (pylablib.core.devio.comm\_backend.IDeviceCommBackend method), 171

close() (pylablib.core.devio.comm\_backend.NetworkDeviceBackend method), 181

close() (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 184

close() (pylablib.core.devio.comm\_backend.RecordedDeviceBackend method), 189

close() (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 176

close() (pylablib.core.devio.comm\_backend.VisaDeviceBackend method), 173

close() (pylablib.core.devio.hid.HIDDevice method), 194

close() (pylablib.core.devio.interface.IDevice method),

- 196
- `close()` (`pylablib.core.devio.SCPi.SCPiDevice` method), 168
- `close()` (`pylablib.core.fileio.location.FolderFileSystemDataLocation` method), 221
- `close()` (`pylablib.core.fileio.location.IDataLocation` method), 219
- `close()` (`pylablib.core.fileio.location.IFileSystemDataLocation` method), 219
- `close()` (`pylablib.core.fileio.location.LocationFile` method), 218
- `close()` (`pylablib.core.fileio.location.OpenedFileLocation` method), 219
- `close()` (`pylablib.core.fileio.location.PrefixedFileSystemDataLocation` method), 221
- `close()` (`pylablib.core.fileio.location.SingleFileSystemDataLocation` method), 220
- `close()` (`pylablib.core.utils.net.ClientSocket` method), 442
- `close()` (`pylablib.devices.Agilent.pressure.XGS600` method), 506
- `close()` (`pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera` method), 514
- `close()` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` method), 510
- `close()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 524
- `close()` (`pylablib.devices.Andor.AndorSDK2.LibraryController` method), 522
- `close()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera` method), 537
- `close()` (`pylablib.devices.Andor.AndorSDK3.LibraryController` method), 534
- `close()` (`pylablib.devices.Andor.Shamrock.LibraryController` method), 544
- `close()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 545
- `close()` (`pylablib.devices.Arcus.performax.GenericPerformaxCamera` method), 551
- `close()` (`pylablib.devices.Arcus.performax.Performax2EXS` method), 557
- `close()` (`pylablib.devices.Arcus.performax.Performax4EXS` method), 555
- `close()` (`pylablib.devices.Arcus.performax.PerformaxDMX` method), 562
- `close()` (`pylablib.devices.Arduino.base.IArduinoDevice` method), 565
- `close()` (`pylablib.devices.Attocube.anc300.ANC300` method), 569
- `close()` (`pylablib.devices.Attocube.anc350.ANC350` method), 572
- `close()` (`pylablib.devices.AWG.generic.GenericAWG` method), 459
- `close()` (`pylablib.devices.AWG.specific.Agilent33220A` method), 468
- `close()` (`pylablib.devices.AWG.specific.Agilent33500` method), 462
- `close()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 480
- `close()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 474
- `close()` (`pylablib.devices.AWG.specific.RigolDG1000` method), 499
- `close()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 487
- `close()` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 493
- `close()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera` method), 578
- `close()` (`pylablib.devices.Basler.pylon.LibraryController` method), 574
- `close()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera` method), 591
- `close()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber` method), 585
- `close()` (`pylablib.devices.Conrad.base.RelayBoard` method), 598
- `close()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 601
- `close()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 604
- `close()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 609
- `close()` (`pylablib.devices.DCAM.DCAM.DCAMCamera` method), 615
- `close()` (`pylablib.devices.DCAM.DCAM.LibraryController` method), 613
- `close()` (`pylablib.devices.ElektroAutomatik.base.PS2000B` method), 623
- `close()` (`pylablib.devices.HighFinesse.wlm.WLM` method), 626
- `close()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 632
- `close()` (`pylablib.devices.IMAQ.IMAQ.IMAQCamera` method), 641
- `close()` (`pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` method), 634
- `close()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera` method), 657
- `close()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera` method), 651
- `close()` (`pylablib.devices.interface.camera.IAttributeCamera` method), 997
- `close()` (`pylablib.devices.interface.camera.IBinROICamera` method), 1015
- `close()` (`pylablib.devices.interface.camera.ICamera` method), 993
- `close()` (`pylablib.devices.interface.camera.IExposureCamera` method), 993

- method), 1006
- `close()` (`pylablib.devices.interface.camera.IGrabberAttribute` method), 1002
- `close()` (`pylablib.devices.interface.camera.IROICamera` method), 1011
- `close()` (`pylablib.devices.interface.stage.IMultiaxisStage` method), 1022
- `close()` (`pylablib.devices.interface.stage.IStage` method), 1020
- `close()` (`pylablib.devices.Keithley.multimeter.Keithley2110` method), 668
- `close()` (`pylablib.devices.KJL.base.KJL300` method), 664
- `close()` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 674
- `close()` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 679
- `close()` (`pylablib.devices.LaserQuantum.base.Finesse` method), 684
- `close()` (`pylablib.devices.Leybold.base.GenericITR` method), 686
- `close()` (`pylablib.devices.Leybold.base.ITR90` method), 688
- `close()` (`pylablib.devices.LighthousePhotonics.base.Sprout` method), 691
- `close()` (`pylablib.devices.Lumel.base.LumelRE72Controller` method), 693
- `close()` (`pylablib.devices.M2.base.ICEBlocDevice` method), 696
- `close()` (`pylablib.devices.M2.emm.EMM` method), 699
- `close()` (`pylablib.devices.M2.solstis.Solstis` method), 706
- `close()` (`pylablib.devices.Mightex.MightexSSeries.LibraryController` method), 707
- `close()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera` method), 708
- `close()` (`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` method), 716
- `close()` (`pylablib.devices.Newport.picomotor.Picomotor8742` method), 738
- `close()` (`pylablib.devices.NI.daq.NIDAQ` method), 718
- `close()` (`pylablib.devices.NKT.interbus.GenericInterbusDevice` method), 726
- `close()` (`pylablib.devices.NKT.interbus.GenericInterbusModule` method), 728
- `close()` (`pylablib.devices.NKT.interbus.IInterbusModule` method), 727
- `close()` (`pylablib.devices.NKT.interbus.InterbusSystem` method), 733
- `close()` (`pylablib.devices.NKT.interbus.SuperKExtremeInterbusModule` method), 729
- `close()` (`pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule` method), 730
- `close()` (`pylablib.devices.NKT.interbus.SuperKSelectDriver` method), 731
- `close()` (`pylablib.devices.NKT.interbus.SuperKSelectInterbusModule` method), 732
- `close()` (`pylablib.devices.Omron.base.OmronE5xCCController` method), 747
- `close()` (`pylablib.devices.Ophir.base.OphirDevice` method), 750
- `close()` (`pylablib.devices.Ophir.base.VegaPowerMeter` method), 753
- `close()` (`pylablib.devices.OZOptics.base.DD100` method), 743
- `close()` (`pylablib.devices.OZOptics.base.EPC04` method), 745
- `close()` (`pylablib.devices.OZOptics.base.OZOpticsDevice` method), 740
- `close()` (`pylablib.devices.OZOptics.base.TF100` method), 742
- `close()` (`pylablib.devices.PCO.SC2.PCOSC2Camera` method), 755
- `close()` (`pylablib.devices.Pfeiffer.base.DPG202` method), 768
- `close()` (`pylablib.devices.Pfeiffer.base.TPG260` method), 766
- `close()` (`pylablib.devices.Photometrics.pvcam.LibraryController` method), 769
- `close()` (`pylablib.devices.Photometrics.pvcam.PvcamCamera` method), 772
- `close()` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` method), 782
- `close()` (`pylablib.devices.PhotonFocus.PhotonFocus.LibraryController` method), 779
- `close()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlow` method), 806
- `close()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQC` method), 789
- `close()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCam` method), 798
- `close()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` method), 815
- `close()` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 819
- `close()` (`pylablib.devices.PhysikInstrumente.base.PIE516` method), 817
- `close()` (`pylablib.devices.PrincetonInstruments.picam.LibraryController` method), 824
- `close()` (`pylablib.devices.PrincetonInstruments.picam.PicamCamera` method), 828
- `close()` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 835
- `close()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera` method), 849
- `close()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` method), 841
- `close()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 841

- method*), 856
- `close()` (*pylablib.devices.SmarAct.MCS2.LibraryController*  
*method*), 868
- `close()` (*pylablib.devices.SmarAct.MCS2.MCS2*  
*method*), 869
- `close()` (*pylablib.devices.SmarAct.scu3d.LibraryController*  
*method*), 873
- `close()` (*pylablib.devices.SmarAct.scu3d.SCU3D*  
*method*), 874
- `close()` (*pylablib.devices.Standa.base.Standa8SMC*  
*method*), 879
- `close()` (*pylablib.devices.Tektronix.base.DPO2000*  
*method*), 895
- `close()` (*pylablib.devices.Tektronix.base.ITektronixScope*  
*method*), 885
- `close()` (*pylablib.devices.Tektronix.base.TDS2000*  
*method*), 888
- `close()` (*pylablib.devices.Thorlabs.elliptec.ElliptecMotor*  
*method*), 914
- `close()` (*pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice*  
*method*), 918
- `close()` (*pylablib.devices.Thorlabs.kinesis.KinesisDevice*  
*method*), 922
- `close()` (*pylablib.devices.Thorlabs.kinesis.KinesisMotor*  
*method*), 932
- `close()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoController*  
*method*), 939
- `close()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor*  
*method*), 936
- `close()` (*pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector*  
*method*), 943
- `close()` (*pylablib.devices.Thorlabs.kinesis.MFF*  
*method*), 925
- `close()` (*pylablib.devices.Thorlabs.misc.GenericPM*  
*method*), 947
- `close()` (*pylablib.devices.Thorlabs.misc.PM160*  
*method*), 950
- `close()` (*pylablib.devices.Thorlabs.serial.FW* *method*),  
958
- `close()` (*pylablib.devices.Thorlabs.serial.FWv1*  
*method*), 962
- `close()` (*pylablib.devices.Thorlabs.serial.MDT69xA*  
*method*), 965
- `close()` (*pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface*  
*method*), 955
- `close()` (*pylablib.devices.Thorlabs.TLCamera.LibraryController*  
*method*), 902
- `close()` (*pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera*  
*method*), 903
- `close()` (*pylablib.devices.Toptica.ibeam.TopticaIBeam*  
*method*), 970
- `close()` (*pylablib.devices.Trinamic.base.TMCM1110*  
*method*), 975
- `close()` (*pylablib.devices.Trinamic.base.TMCMx110*  
*method*), 976
- `close()` (*pylablib.devices.uc480.uc480.UC480Camera*  
*method*), 1025
- `close()` (*pylablib.devices.utils.load\_lib.LibraryController*  
*method*), 1033
- `close()` (*pylablib.devices.Voltcraft.multimeter.VC7055*  
*method*), 982
- `close()` (*pylablib.devices.Voltcraft.multimeter.VC880*  
*method*), 986
- `close()` (*pylablib.devices.Windows.joystick.Joystick*  
*method*), 988
- `close_connection()` (*py-*  
*lablib.core.utils.ipc.SharedMemIPCTable*  
*method*), 437
- `close_result` (*pylablib.devices.utils.load\_lib.TLibraryCloseResult*  
*attribute*), 1033
- `cls` (*pylablib.core.utils.string.TConversionClass* *at-*  
*tribute*), 451
- `cmp_dirs()` (*in module pylablib.core.utils.files*), 417
- `cmp_package_version()` (*in module py-*  
*lablib.core.utils.module*), 437
- `cmp_versions()` (*in module pylablib.core.utils.module*),  
437
- `coarse_tune_wavelength()` (*py-*  
*lablib.devices.M2.solstis.Solstis* *method*),  
702
- `Cobolt` (*class in pylablib.devices.Hubner.Cobolt*), 630
- `coeff` (*pylablib.devices.Lakeshore.base.TLakeshore218CurveHeader*  
*attribute*), 672
- `collect()` (*pylablib.core.utils.dictionary.Dictionary*  
*method*), 382
- `collect()` (*pylablib.core.utils.dictionary.DictionaryPointer*  
*method*), 388
- `collect()` (*pylablib.core.utils.dictionary.FilterTree*  
*method*), 404
- `collect()` (*pylablib.core.utils.dictionary.PrefixTree*  
*method*), 396
- `collect_into_bins()` (*in module py-*  
*lablib.core.dataproc.filters*), 139
- `color_format` (*pylablib.devices.Thorlabs.TLCamera.TColorFormat*  
*attribute*), 903
- `color_space` (*pylablib.devices.Thorlabs.TLCamera.TColorFormat*  
*attribute*), 903
- `column()` (*pylablib.core.dataproc.table\_wrap.Array2DWrapper*  
*method*), 158
- `column()` (*pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper*  
*method*), 160
- `column()` (*pylablib.core.dataproc.table\_wrap.I2DWrapper*  
*method*), 156
- `columns_replaced()` (*py-*  
*lablib.core.dataproc.table\_wrap.Array2DWrapper*  
*method*), 158
- `columns_replaced()` (*py-*  
*lablib.core.dataproc.table\_wrap.DataFrame2DWrapper*  
*method*), 158



method), 161

columns\_replaced() (pylablib.core.dataproc.table\_wrap.I2DWrapper method), 156

columns\_to\_table() (in module pylablib.core.fileio.parse\_csv), 223

combine\_conn() (pylablib.core.devio.comm\_backend.FT232RLDevice class method), 180

combine\_conn() (pylablib.core.devio.comm\_backend.HIDDevice class method), 188

combine\_conn() (pylablib.core.devio.comm\_backend.IDevice class method), 171

combine\_conn() (pylablib.core.devio.comm\_backend.NetworkDevice class method), 182

combine\_conn() (pylablib.core.devio.comm\_backend.PyUSBDevice class method), 185

combine\_conn() (pylablib.core.devio.comm\_backend.Recorder class method), 190

combine\_conn() (pylablib.core.devio.comm\_backend.SerialDevice class method), 177

combine\_conn() (pylablib.core.devio.comm\_backend.VisaDevice class method), 174

combine\_dictionaries() (in module pylablib.core.utils.dictionary), 394

combine\_diff() (in module pylablib.core.utils.files), 417

CombinedParameterClass (class in pylablib.core.devio.interface), 201

ComboBox (class in pylablib.core.gui.widgets.combo\_box), 234

ComboBoxValueHandler (class in pylablib.core.gui.value\_handling), 323

comm (pylablib.devices.Conrad.base.RelayBoard.TMessage attribute), 598

comm (pylablib.devices.Thorlabs.elliptec.ElliptecMotor.Comm attribute), 913

comm (pylablib.devices.Trinamic.base.TTMCM1110ReplyData attribute), 972

comm() (pylablib.devices.Arduino.base.IArduinoDevice method), 564

comm() (pylablib.devices.ElektroAutomatik.base.PS2000B method), 623

comm() (pylablib.devices.KJL.base.KJL300 method), 663

comm() (pylablib.devices.Pfeiffer.base.DPG202 method), 767

comm() (pylablib.devices.Pfeiffer.base.TPG260 method), 764

comm\_paused() (pylablib.core.thread.controller.QTaskThread method), 356

command (pylablib.core.thread.controller.QTaskThread.TCommand attribute), 351

common (pylablib.core.utils.dictionary.DictionaryIntersection attribute), 385

compare\_lists() (in module pylablib.core.utils.general), 427

compilation\_number (pylablib.devices.HighFinesse.wlm.TDeviceInfo attribute), 625

complex\_lorentzian\_k() (in module pylablib.core.dataproc.specfunc), 151

concrete\_backend\_layout() (in module pylablib.core.gui.utils), 310

configure() (pylablib.devices.LighthousePhotonics.base.TDeviceInfo attribute), 690

configure\_trigger\_in() (pylablib.devices.AlliedVision.Bonito.BonitoIMACamera method), 514

configure\_trigger\_in() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 641

configure\_trigger\_in() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 635

configure\_trigger\_in() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera method), 789

configure\_trigger\_out() (pylablib.devices.AlliedVision.Bonito.BonitoIMACamera method), 514

configure\_trigger\_out() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 642

configure\_trigger\_out() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 636

configure\_trigger\_out() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera method), 789

connect() (pylablib.core.gui.value\_handling.VirtualValueChangedSignal method), 312

connect() (pylablib.core.utils.net.ClientSocket method), 442

connect\_device\_service() (in module pylablib.core.utils.rpyc\_utils), 448

connect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.CheckboxValueHandler method), 320

connect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ComboBoxValueHandler method), 323

connect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.IBoolValueHandler method), 319

connect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ISingleValueHandler method), 316

connect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.IValueHandler method), 316

method), 312

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.LabelValueHandler method), 318

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.LineEditValueHandler method), 317

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.ProgressBarValueHandler method), 324

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.PropertyValueHandler method), 314

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.PushButtonValueHandler method), 321

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.StandardValueHandler method), 315

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.ToolButtonValueHandler method), 322

connect\_value\_changed\_handler() (py-lablib.core.gui.value\_handling.VirtualValueHandler method), 313

connect\_wavemeter() (py-lablib.devices.M2.solstis.Solstis method), 701

ConradBackendError, 597

ConradError, 597

cons\_error (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

cons\_excluded (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

cons\_included (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

cons\_novalid (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

cons\_permanent (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

cons\_type (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 826

constant() (in module pylablib.core.utils.numerical), 444

contained\_value\_changed (py-lablib.core.gui.widgets.container.IQContainer attribute), 236

contained\_value\_changed (py-lablib.core.gui.widgets.container.IQWidgetContainer attribute), 243

contained\_value\_changed (py-lablib.core.gui.widgets.container.QContainer attribute), 239

contained\_value\_changed (py-lablib.core.gui.widgets.container.QDialogContainer attribute), 257

contained\_value\_changed (py-lablib.core.gui.widgets.container.QFrameContainer attribute), 252

contained\_value\_changed (py-lablib.core.gui.widgets.container.QGroupBoxContainer attribute), 262

contained\_value\_changed (py-lablib.core.gui.widgets.container.QScrollAreaContainer attribute), 270

contained\_value\_changed (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer attribute), 266

contained\_value\_changed (py-lablib.core.gui.widgets.container.QTabContainer attribute), 273

contained\_value\_changed (py-lablib.core.gui.widgets.container.QWidgetContainer attribute), 248

contained\_value\_changed (py-lablib.core.gui.widgets.param\_table.ParamTable attribute), 293

contained\_value\_changed (py-lablib.core.gui.widgets.param\_table.StatusTable attribute), 303

contains() (pylablib.core.dataproc.utils.Range method), 164

continuous (pylablib.devices.NI.daq.TVoltageOutputClockParameters attribute), 718

ControlError (pylablib.devices.LighthousePhotonics.base.TWorkHours attribute), 690

control\_error (pylablib.devices.Andor.AndorSDK2.TDeviceInfo attribute), 523

conv (pylablib.core.utils.string.TConversionClass attribute), 451

conv() (pylablib.core.utils.ctypes\_wrap.CStructWrapper attribute), 475

convert\_columns() (py-lablib.core.fileio.parse\_csv.ChunksAccumulator method), 223

convert\_frequency\_units() (in module py-lablib.core.utils.units), 454

convert\_from\_str() (py-lablib.core.devio.data\_format.DataFormat method), 193

convert\_image\_indexing() (in module py-lablib.core.dataproc.image), 147

convert\_length\_units() (in module py-lablib.core.utils.units), 454

convert\_power\_units() (in module py-lablib.core.utils.units), 454

convert\_shape\_indexing() (in module py-

`lablib.core.dataproc.image`), 147  
`convert_time_units()` (in module `pylablib.core.utils.units`), 454  
`convert_to_str()` (in module `pylablib.core.devio.data_format.DataFormat` method), 194  
`convolution_filter()` (in module `pylablib.core.dataproc.filters`), 137  
`convolve1d()` (in module `pylablib.core.dataproc.filters`), 137  
`cooldown()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` attribute), 180  
`cooldown()` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` attribute), 188  
`cooldown()` (`pylablib.core.devio.comm_backend.IDeviceBackend` attribute), 171  
`cooldown()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` attribute), 182  
`cooldown()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` attribute), 185  
`cooldown()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` attribute), 190  
`cooldown()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` attribute), 177  
`cooldown()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` attribute), 174  
`copy()` (`pylablib.core.dataproc.ctransform_fallback.CLinear2DTransform` method), 134  
`copy()` (`pylablib.core.dataproc.image.ROI` method), 148  
`copy()` (`pylablib.core.dataproc.table_wrap.Array1DWrapper` method), 154  
`copy()` (`pylablib.core.dataproc.table_wrap.Array2DWrapper` method), 158  
`copy()` (`pylablib.core.dataproc.table_wrap.DataFrame2DWrapper` method), 160  
`copy()` (`pylablib.core.dataproc.table_wrap.I1DWrapper` method), 153  
`copy()` (`pylablib.core.dataproc.table_wrap.I2DWrapper` method), 156  
`copy()` (`pylablib.core.dataproc.table_wrap.IGenWrapper` method), 152  
`copy()` (`pylablib.core.dataproc.table_wrap.Series1DWrapper` method), 155  
`copy()` (`pylablib.core.fileio.location.LocationName` method), 218  
`copy()` (`pylablib.core.utils.dictionary.Dictionary` method), 382  
`copy()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 388  
`copy()` (`pylablib.core.utils.dictionary.FilterTree` method), 403  
`copy()` (`pylablib.core.utils.dictionary.PrefixShortcutTree` method), 411  
`copy()` (`pylablib.core.utils.dictionary.PrefixTree` method), 394  
`copy()` (`pylablib.core.utils.functions.FunctionSignature` method), 421  
`copy_array_chunks()` (in module `pylablib.core.utils.nbtools`), 439  
`copy_array_strided()` (in module `pylablib.core.utils.nbtools`), 439  
`copy_dir()` (in module `pylablib.core.utils.files`), 416  
`copy_file()` (in module `pylablib.core.utils.files`), 414  
`corr_number` (`pylablib.devices.Attocube.anc350.ANC350.Telegram` attribute), 570  
`correction_matrix` (`pylablib.devices.Thorlabs.TLCamera.TColorInfo` attribute), 903  
`countdown()` (`pylablib.core.utils.general.Countdown` class in `pylablib.core.utils.general`), 429  
`countdown()` (`pylablib.devices.Keithley.multimeter.TAveragingParameters` attribute), 666  
`countdown()` (`pylablib.devices.Tektronix.base.TTriggerParameters` attribute), 881  
`create_backend1()` (in module `pylablib.core.utils.indexing`), 433  
`create_backend2()` (in module `pylablib.core.utils.crc`), 372  
`create_indicator_handler()` (in module `pylablib.core.gui.value_handling`), 326  
`create_value_handler()` (in module `pylablib.core.gui.value_handling`), 325  
`Cryocon1x` (class in `pylablib.devices.Cryocon.base`), 600  
`CryoconBackendError`, 599  
`CryoconError`, 599  
`CryomagneticsBackendError`, 604  
`CryomagneticsError`, 604  
`cs` (`pylablib.core.thread.controller.QTaskThread` attribute), 350  
`csi` (`pylablib.core.thread.controller.QTaskThread` attribute), 350  
`css` (`pylablib.core.thread.controller.QTaskThread` attribute), 350  
`CStructWrapper` (class in `pylablib.core.utils.ctypes_wrap`), 375  
`CSVTableInputFileFormat` (class in `pylablib.core.fileio.loadfile`), 211  
`CSVTableOutputFileFormat` (class in `pylablib.core.fileio.savefile`), 225  
`curr_idx` (`pylablib.devices.Ophir.base.TRangeInfo` attribute), 751  
`curr_idx` (`pylablib.devices.Ophir.base.TWavelengthInfo` attribute), 751  
`curr_range` (`pylablib.devices.Ophir.base.TRangeInfo` attribute), 751  
`curr_wavelength` (`pylablib.devices.Ophir.base.TWavelengthInfo` attribute), 751

attribute), 751  
 current (pylablib.devices.ElektroAutomatik.base.TOutputLimits attribute), 622  
 current (pylablib.devices.Thorlabs.elliptec.TMotorInfo attribute), 912  
 current\_controller() (in module pylablib.core.thread.threadprop), 371  
 cut\_out\_regions() (in module pylablib.core.dataproc.utils), 164  
 cut\_to\_range() (in module pylablib.core.dataproc.utils), 164  
 cycles\_done (pylablib.devices.Andor.AndorSDK2.TAcqProc attribute), 523

## D

d (pylablib.devices.Thorlabs.kinesis.TQuadDetectorPIDParams attribute), 941  
 d2func (pylablib.devices.Voltcraft.multimeter.TVC880Reading attribute), 984  
 data (pylablib.core.utils.ipc.TPipeMsg attribute), 435  
 data (pylablib.devices.Attocube.anc350.ANC350.Reply attribute), 570  
 data (pylablib.devices.Attocube.anc350.ANC350.Telegram attribute), 570  
 data (pylablib.devices.Conrad.base.RelayBoard.TMessage attribute), 598  
 data (pylablib.devices.ElektroAutomatik.base.PS2000B.TTelement attribute), 623  
 data (pylablib.devices.Modbus.modbus.TModbusFrame attribute), 715  
 data (pylablib.devices.Thorlabs.elliptec.ElliptecMotor.Command attribute), 913  
 data (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice.Command attribute), 917  
 DataFile (class in pylablib.core.fileio.datafile), 202  
 DataFormat (class in pylablib.core.devio.data\_format), 193  
 DataFrame2DWrapper (class in pylablib.core.dataproc.table\_wrap), 159  
 DataFrame2DWrapper.ColumnAccessor (class in pylablib.core.dataproc.table\_wrap), 159  
 DataFrame2DWrapper.RowAccessor (class in pylablib.core.dataproc.table\_wrap), 159  
 DataFrame2DWrapper.TableAccessor (class in pylablib.core.dataproc.table\_wrap), 160  
 date (pylablib.devices.uc480.uc480.TDeviceInfo attribute), 1023  
 day (pylablib.devices.uc480.uc480.TTimestamp attribute), 1024  
 DCAMAttribute (class in pylablib.devices.DCAM.DCAM), 613  
 DCAMCamera (class in pylablib.devices.DCAM.DCAM), 615  
 DD100 (class in pylablib.devices.OZOptics.base), 743  
 deactivation\_control (pylablib.devices.Pfeiffer.base.TTPG260GaugeControlSettings attribute), 764  
 deallocate() (pylablib.devices.interface.camera.ChunkBufferManager method), 995  
 deallocate() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesC method), 710  
 deallocate() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusS method), 797  
 deallocate() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCam method), 848  
 deallocate() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFra method), 843  
 deallocate\_buffers() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.BufferMan method), 539  
 decel (pylablib.devices.Standa.base.TMoveParams attribute), 877  
 decimate() (in module pylablib.core.dataproc.filters), 138  
 decimate\_datasets() (in module pylablib.core.dataproc.filters), 139  
 decimate\_full() (in module pylablib.core.dataproc.filters), 139  
 decllen\_bo (pylablib.core.utils.net.ClientSocket attribute), 441  
 decllen\_ll (pylablib.core.utils.net.ClientSocket attribute), 442  
 default (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 771  
 default (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 826  
 default\_white\_balance\_matrix (pylablib.devices.Thorlabs.TLCamera.TColorInfo attribute), 903  
 DefaultFrameTransferError, 989  
 del\_entry() (pylablib.core.utils.dictionary.Dictionary method), 378  
 del\_entry() (pylablib.core.utils.dictionary.DictionaryPointer method), 388  
 del\_entry() (pylablib.core.utils.dictionary.FilterTree method), 405  
 del\_entry() (pylablib.core.utils.dictionary.PrefixTree method), 397  
 del\_fit\_parameters() (pylablib.core.dataproc.fitting.Fitter method), 142  
 del\_fixed\_parameters() (pylablib.core.dataproc.fitting.Fitter method), 142  
 delattr\_call() (in module pylablib.core.utils.functions), 423  
 delaydef() (in module pylablib.core.utils.functions), 424



- `delete_layout_item()` (in module `pylablib.core.gui.utils`), 309
- `delete_thread_method()` (`pylablib.core.thread.controller.QTaskThread` method), 357
- `delete_thread_method()` (`pylablib.core.thread.controller.QThreadController` method), 347
- `delete_variable()` (`pylablib.core.thread.controller.QTaskThread` method), 358
- `delete_variable()` (`pylablib.core.thread.controller.QThreadController` method), 347
- `delete_widget()` (in module `pylablib.core.gui.utils`), 309
- `deregister()` (`pylablib.devices.Basler.pylon.BaslerPylonCameraManager` method), 579
- `desc` (`pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo` attribute), 839
- `description` (`pylablib.devices.Basler.pylon.BaslerPylonCameraManager` attribute), 576
- `description` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxDevice` attribute), 649
- `dest` (`pylablib.devices.NKT.interbus.TInterbusTelegram` attribute), 725
- `dest` (`pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice` attribute), 917
- `dest` (`pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice` attribute), 917
- `detach()` (`pylablib.core.utils.dictionary.Dictionary` method), 382
- `detach()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 388
- `detach()` (`pylablib.core.utils.dictionary.FilterTree` method), 405
- `detach()` (`pylablib.core.utils.dictionary.PrefixTree` method), 397
- `detect_binary_file()` (in module `pylablib.core.fileio.loadfile_utils`), 216
- `detect_file_format()` (`pylablib.core.fileio.loadfile.BinaryTableInputFileFormat` static method), 212
- `detect_file_format()` (`pylablib.core.fileio.loadfile.CSVTableInputFileFormat` static method), 211
- `detect_file_format()` (`pylablib.core.fileio.loadfile.DictionaryInputFileFormat` static method), 212
- `detect_file_format()` (`pylablib.core.fileio.loadfile.IInputFileFormat` static method), 210
- `detect_file_format()` (`pylablib.core.fileio.loadfile.ITextInputFileFormat` static method), 211
- `detect_textfile_type()` (in module `pylablib.core.fileio.loadfile_utils`), 216
- `dev_id` (`pylablib.devices.uc480.uc480.TCameraInfo` attribute), 1022
- `devclass` (`pylablib.devices.Basler.pylon.TCameraInfo` attribute), 575
- `devclass` (`pylablib.devices.Basler.pylon.TDeviceInfo` attribute), 577
- `device` (`pylablib.devices.Sirah.Matisse.TScanParameters` attribute), 856
- `device_id` (`pylablib.devices.SmarAct.scu3d.TDeviceInfo` attribute), 874
- `device_info` (`pylablib.devices.Leybold.base.TUpdateValue` attribute), 685
- `DeviceBackendError`, 170
- `DeviceBufferManager`, 170
- `DeviceFT232Error`, 178
- `DeviceHIDError`, 186
- `DeviceNetworkError`, 181
- `DeviceRecordedError`, 189
- `DeviceSerialError`, 175
- `DeviceService` (class in `pylablib.core.utils.rpyc_utils`), 447
- `DeviceUSBError`, 183
- `DeviceVisaError`, 172
- `dimension` (`pylablib.devices.Basler.pylon.TCameraInfo` attribute), 575
- `dimension` (`pylablib.devices.Basler.pylon.TDeviceInfo` attribute), 577
- `dict_to_object_local()` (in module `pylablib.core.utils.dictionary`), 411
- `DictEntryBuilder` (class in `pylablib.core.fileio.dict_entry`), 203
- `DictEntryParser` (class in `pylablib.core.fileio.dict_entry`), 203
- `Dictionary` (class in `pylablib.core.utils.dictionary`), 377
- `DictionaryDiff` (class in `pylablib.core.utils.dictionary`), 385
- `DictionaryInputFileFormat` (class in `pylablib.core.fileio.loadfile`), 211
- `DictionaryIntersection` (class in `pylablib.core.utils.dictionary`), 385
- `DictionaryNode` (class in `pylablib.core.utils.dictionary`), 411
- `DictionaryOutputFileFormat` (class in `pylablib.core.fileio.savefile`), 226
- `DictionaryPointer` (class in `pylablib.core.utils.dictionary`), 386
- `diff()` (`pylablib.core.utils.dictionary.Dictionary` method), 384
- `diff()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 388
- `diff()` (`pylablib.core.utils.dictionary.FilterTree` method), 388

- method), 405
- diff() (pylablib.core.utils.dictionary.PrefixTree method), 397
- diff\_flatdict() (pylablib.core.utils.dictionary.Dictionary static method), 384
- diff\_flatdict() (pylablib.core.utils.dictionary.DictionaryPointer static method), 388
- diff\_flatdict() (pylablib.core.utils.dictionary.FilterTree static method), 405
- diff\_flatdict() (pylablib.core.utils.dictionary.PrefixTree static method), 397
- differentiate() (in module pylablib.core.dataproc.filters), 138
- diode (pylablib.devices.Toptica.ibeam.TTemperatures attribute), 969
- dir\_empty() (in module pylablib.core.utils.files), 415
- disable\_axis() (pylablib.devices.Attocube.anc300.ANC300 method), 567
- disable\_axis() (pylablib.devices.Attocube.anc350.ANC350 method), 571
- disable\_callback() (pylablib.devices.Mightex.MightexSSeries.MightexSSeries method), 709
- disconnect() (pylablib.core.gui.value\_handling.VirtualValueHandler method), 312
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.CheckboxValueHandler method), 320
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ComboBoxValueHandler method), 323
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.IBoolValueHandler method), 319
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ISingleValueHandler method), 316
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.IValueHandler method), 312
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.LabelValueHandler method), 318
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.LineEditValueHandler method), 317
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ProgressBarValueHandler method), 324
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.PropertyValueHandler method), 314
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.PushButtonValueHandler method), 321
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.StandardValueHandler method), 315
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.ToolButtonValueHandler method), 322
- disconnect\_value\_changed\_handler() (pylablib.core.gui.value\_handling.VirtualValueHandler method), 313
- disconnect\_wavemeter() (pylablib.devices.M2.solstis.Solstis method), 701
- display\_name (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576
- display\_name (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649
- display\_units (pylablib.devices.Leybold.base.TUpdateValue attribute), 685
- disps (pylablib.devices.Voltcraft.multimeter.TVC880Reading attribute), 985
- dlc\_conversion (pylablib.devices.SmarAct.scu3d.TDeviceInfo attribute), 874
- dlc\_conversion (pylablib.devices.uc480.uc480.TDeviceInfo attribute), 1023
- dnodet (pylablib.devices.ElektroAutomatik.base.PS2000B.TTelegram attribute), 623
- doc\_inherit() (in module pylablib.core.utils.general), 429
- docstring() (pylablib.core.devio.interface.CombinedParameterClass method), 202
- docstring() (pylablib.core.devio.interface.EnumParameterClass method), 201
- docstring() (pylablib.core.devio.interface.FunctionParameterClass method), 201
- docstring() (pylablib.core.devio.interface.ICheckingParameterClass method), 198
- docstring() (pylablib.core.devio.interface.IEnumParameterClass method), 200
- docstring() (pylablib.core.devio.interface.IParameterClass method), 197
- docstring() (pylablib.core.devio.interface.RangeParameterClass method), 198
- done\_notify() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330
- done\_notify() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 332
- done\_notify() (pylablib.core.thread.notifier.ISkippableNotifier method), 366
- done\_notify() (pylablib.core.thread.synchronizing.QThreadNotifier method), 366

- method), 367
- done\_wait() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330
- done\_wait() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331
- done\_wait() (pylablib.core.thread.notifier.ISkippableNotifier method), 366
- done\_wait() (pylablib.core.thread.synchronizing.QThreadNotifier method), 367
- DP1116A (class in pylablib.devices.Rigol.power\_supply), 834
- DPG202 (class in pylablib.devices.Pfeiffer.base), 767
- DPO2000 (class in pylablib.devices.Tektronix.base), 895
- driver (pylablib.devices.Standa.base.TEngineType attribute), 876
- DummyResource (class in pylablib.core.utils.general), 427
- dump() (in module pylablib.core.utils.strdump), 449
- dump() (pylablib.core.utils.strdump.StrDumper method), 448
- dumper (in module pylablib.core.utils.strdump), 448
- dumps() (in module pylablib.core.utils.strdump), 449
- dumps() (pylablib.core.utils.strdump.StrDumper method), 448
- DuplicateControllerThreadError, 369
- ## E
- ElektroAutomatikBackendError, 622
- ElektroAutomatikError, 621
- ElliptecMotor (class in pylablib.devices.Thorlabs.elliptec), 912
- ElliptecMotor.CommData (class in pylablib.devices.Thorlabs.elliptec), 913
- emission (pylablib.devices.Leybold.base.TITR90Status attribute), 687
- EMM (class in pylablib.devices.M2.emm), 697
- empty\_object\_property() (in module pylablib.core.utils.functions), 424
- enable (pylablib.devices.Lakeshore.base.TLakeshore370RangeSetting attribute), 677
- enable() (pylablib.devices.Hubner.Cobolt.Cobolt method), 630
- enable() (pylablib.devices.LaserQuantum.base.Finesse method), 683
- enable() (pylablib.devices.LighthousePhotonics.base.SproutG method), 691
- enable() (pylablib.devices.Pfeiffer.base.TPG260 method), 765
- enable() (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 969
- enable\_absolute\_mode() (pylablib.devices.Arcus.performax.Performax2EXStage method), 557
- enable\_absolute\_mode() (pylablib.devices.Arcus.performax.Performax4EXStage method), 553
- enable\_absolute\_mode() (pylablib.devices.Arcus.performax.PerformaxDMXJSAStage method), 560
- enable\_analog\_modulation() (pylablib.devices.Hubner.Cobolt.Cobolt method), 631
- enable\_autorange() (pylablib.devices.Thorlabs.misc.GenericPM method), 946
- enable\_autorange() (pylablib.devices.Thorlabs.misc.PM160 method), 950
- enable\_autorange() (pylablib.devices.Voltcraft.multimeter.VC7055 method), 981
- enable\_autorange() (pylablib.devices.Voltcraft.multimeter.VC880 method), 985
- enable\_axis() (pylablib.devices.Arcus.performax.Performax2EXStage method), 557
- enable\_axis() (pylablib.devices.Arcus.performax.Performax4EXStage method), 553
- enable\_axis() (pylablib.devices.Arcus.performax.PerformaxDMXJSAStage method), 560
- enable\_axis() (pylablib.devices.Attocube.anc300.ANC300 method), 567
- enable\_axis() (pylablib.devices.Attocube.anc350.ANC350 method), 571
- enable\_burst() (pylablib.devices.AWG.generic.GenericAWG method), 457
- enable\_burst() (pylablib.devices.AWG.specific.Agilent33220A method), 468
- enable\_burst() (pylablib.devices.AWG.specific.Agilent33500 method), 462
- enable\_burst() (pylablib.devices.AWG.specific.InstekAFG2000 method), 480
- enable\_burst() (pylablib.devices.AWG.specific.InstekAFG2225 method), 474
- enable\_burst() (pylablib.devices.AWG.specific.RigolDG1000 method), 499
- enable\_burst() (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 487
- enable\_burst() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 493
- enable\_callback() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera.Re method), 709
- enable\_CFR() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus method), 783
- enable\_CFR() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusB method), 806

`enable_CFR()` (`pylablib.devices.PhotonFocus.PhotonFocus.enable_CFR()` (pylablib.devices.PhotonFocus.PhotonFocus.enable\_CFR() method), 789  
`enable_CFR()` (`pylablib.devices.PhotonFocus.PhotonFocus.enable_CFR()` (pylablib.devices.PhotonFocus.PhotonFocus.enable\_CFR() method), 798  
`enable_channel()` (`pylablib.devices.Tektronix.base.DPO2000.enable_channel()` (pylablib.devices.Tektronix.base.DPO2000.enable\_channel() method), 895  
`enable_channel()` (`pylablib.devices.Tektronix.base.ITektronixScope.enable_channel()` (pylablib.devices.Tektronix.base.ITektronixScope.enable\_channel() method), 883  
`enable_channel()` (`pylablib.devices.Tektronix.base.TDS2000.enable_channel()` (pylablib.devices.Tektronix.base.TDS2000.enable\_channel() method), 888  
`enable_channel()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoController.enable_channel()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController.enable\_channel() method), 938  
`enable_channel()` (`pylablib.devices.Topica.ibeam.TopicalIBeam.enable_channel()` (pylablib.devices.Topica.ibeam.TopicalIBeam.enable\_channel() method), 969  
`enable_channels()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor.enable_channels()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor.enable\_channels() method), 934  
`enable_cooling()` (`pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable_cooling()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable\_cooling() method), 906  
`enable_digital_modulation()` (`pylablib.devices.Hubner.Cobolt.Cobolt.enable_digital_modulation()` (pylablib.devices.Hubner.Cobolt.Cobolt.enable\_digital\_modulation() method), 631  
`enable_drift_compensation()` (`pylablib.devices.PhysikInstrumente.base.PIE516.enable_drift_compensation()` (pylablib.devices.PhysikInstrumente.base.PIE516.enable\_drift\_compensation() method), 816  
`enable_frame_transfer_mode()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera.enable_frame_transfer_mode()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera.enable\_frame\_transfer\_mode() method), 528  
`enable_led()` (`pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable_led()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable\_led() method), 906  
`enable_limit_errors()` (`pylablib.devices.Arcus.performax.Performax2EXStage.enable_limit_errors()` (pylablib.devices.Arcus.performax.Performax2EXStage.enable\_limit\_errors() method), 557  
`enable_limit_errors()` (`pylablib.devices.Arcus.performax.Performax4EXStage.enable_limit_errors()` (pylablib.devices.Arcus.performax.Performax4EXStage.enable\_limit\_errors() method), 553  
`enable_metadata()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.enable_metadata()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.enable\_metadata() method), 539  
`enable_metadata()` (`pylablib.devices.Photometrics.pvcam.PvcamCamera.enable_metadata()` (pylablib.devices.Photometrics.pvcam.PvcamCamera.enable\_metadata() method), 773  
`enable_metadata()` (`pylablib.devices.PrincetonInstruments.picam.PicamCamera.enable_metadata()` (pylablib.devices.PrincetonInstruments.picam.PicamCamera.enable\_metadata() method), 828  
`enable_nir_boost()` (`pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable_nir_boost()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.enable\_nir\_boost() method), 906  
`enable_online()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController.enable_online()` (pylablib.devices.PhysikInstrumente.base.GenericPIController.enable\_online() method), 815  
`enable_online()` (`pylablib.devices.PhysikInstrumente.base.PIE515.enable_online()` (pylablib.devices.PhysikInstrumente.base.PIE515.enable\_online() method), 819  
`enable_online()` (`pylablib.devices.PhysikInstrumente.base.PIE516.enable_online()` (pylablib.devices.PhysikInstrumente.base.PIE516.enable\_online() method), 817  
`enable_output()` (`pylablib.devices.AWG.generic.GenericAWG.enable_output()` (pylablib.devices.AWG.generic.GenericAWG.enable\_output() method), 456  
`enable_output()` (`pylablib.devices.AWG.specific.Agilent33220A.enable_output()` (pylablib.devices.AWG.specific.Agilent33220A.enable\_output() method), 468  
`enable_output()` (`pylablib.devices.AWG.specific.Agilent33500.enable_output()` (pylablib.devices.AWG.specific.Agilent33500.enable\_output() method), 462  
`enable_output()` (`pylablib.devices.AWG.specific.InstekAFG2000.enable_output()` (pylablib.devices.AWG.specific.InstekAFG2000.enable\_output() method), 480  
`enable_output()` (`pylablib.devices.AWG.specific.InstekAFG2225.enable_output()` (pylablib.devices.AWG.specific.InstekAFG2225.enable\_output() method), 475  
`enable_output()` (`pylablib.devices.AWG.specific.RigolDG1000.enable_output()` (pylablib.devices.AWG.specific.RigolDG1000.enable\_output() method), 499  
`enable_output()` (`pylablib.devices.AWG.specific.RSInstekAFG21000.enable_output()` (pylablib.devices.AWG.specific.RSInstekAFG21000.enable\_output() method), 487  
`enable_output()` (`pylablib.devices.AWG.specific.TektronixAFG1000.enable_output()` (pylablib.devices.AWG.specific.TektronixAFG1000.enable\_output() method), 493  
`enable_output()` (`pylablib.devices.ElektroAutomatik.base.PS2000B.enable_output()` (pylablib.devices.ElektroAutomatik.base.PS2000B.enable\_output() method), 624  
`enable_output()` (`pylablib.devices.Rigol.power_supply.DP1116A.enable_output()` (pylablib.devices.Rigol.power\_supply.DP1116A.enable\_output() method), 834  
`enable_ovp()` (`pylablib.devices.Rigol.power_supply.DP1116A.enable_ovp()` (pylablib.devices.Rigol.power\_supply.DP1116A.enable\_ovp() method), 835  
`enable_pixel_correction()` (`pylablib.devices.PCO.SC2.PCOSC2Camera.enable_pixel_correction()` (pylablib.devices.PCO.SC2.PCOSC2Camera.enable\_pixel\_correction() method), 758  
`enable_raw_readout()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera.enable_raw_readout()` (pylablib.devices.Basler.pylon.BaslerPylonCamera.enable\_raw\_readout() method), 580  
`enable_raw_readout()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.enable_raw_readout()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.enable\_raw\_readout() method), 657  
`enable_raw_readout()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.enable_raw_readout()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.enable\_raw\_readout() method), 657



- method), 653
- enable\_remote() (py-lablib.devices.ElektroAutomatik.base.PS2000B method), 624
- enable\_servo() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 820
- enable\_servo() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 816
- enable\_status\_line() (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 514
- enable\_status\_line() (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 509
- enable\_status\_line() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 784
- enable\_status\_line() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 806
- enable\_status\_line() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 789
- enable\_status\_line() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 798
- enable\_switcher\_channel() (py-lablib.devices.HighFinesse.wlm.WLM method), 628
- enable\_sync\_output() (py-lablib.devices.AWG.generic.GenericAWG method), 456
- enable\_sync\_output() (py-lablib.devices.AWG.specific.Agilent33220A method), 468
- enable\_sync\_output() (py-lablib.devices.AWG.specific.Agilent33500 method), 462
- enable\_sync\_output() (py-lablib.devices.AWG.specific.InstekAFG2000 method), 480
- enable\_sync\_output() (py-lablib.devices.AWG.specific.InstekAFG2225 method), 475
- enable\_sync\_output() (py-lablib.devices.AWG.specific.RigolDG1000 method), 499
- enable\_sync\_output() (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 487
- enable\_sync\_output() (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 493
- enable\_terascan\_updates() (py-lablib.devices.M2.emm.EMM method), 698
- enable\_terascan\_updates() (py-lablib.devices.M2.solstis.Solstis method), 704
- enable\_trigger\_output() (py-lablib.devices.AWG.generic.GenericAWG method), 458
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.Agilent33220A method), 468
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.Agilent33500 method), 462
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.InstekAFG2000 method), 481
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.InstekAFG2225 method), 475
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.RigolDG1000 method), 499
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 487
- enable\_trigger\_output() (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 493
- enable\_updates() (py-lablib.devices.Attocube.anc350.ANC350 method), 570
- enable\_velocity\_control() (py-lablib.devices.PhysikInstrumente.base.PIE516 method), 816
- enabled (pylablib.devices.ElektroAutomatik.base.TStatus attribute), 622
- enabled (pylablib.devices.Keithley.multimeter.TAveragingParameters attribute), 666
- enabled (pylablib.devices.Lakeshore.base.TLakeshore218FilterSettings attribute), 672
- enabled (pylablib.devices.Lakeshore.base.TLakeshore370FilterSettings attribute), 677
- encoder (pylablib.devices.Standa.base.TFullState attribute), 877
- engine (pylablib.devices.Standa.base.TEngineType attribute), 876
- ensure\_dir() (in module pylablib.core.utils.files), 414
- ensure\_dir\_singlelevel() (in module py-lablib.core.utils.files), 414
- EnumLabel (class in pylablib.core.gui.widgets.label), 277
- EnumParameterClass (class in py-lablib.core.devio.interface), 200
- eof() (in module pylablib.core.utils.files), 412
- EPC04 (class in pylablib.devices.OZOptics.base), 744

errno (pylablib.core.thread.threadprop.TimeoutThreadError attribute), 369  
 errno (pylablib.core.utils.net.SocketError attribute), 440  
 errno (pylablib.core.utils.net.SocketTimeout attribute), 440  
 Error (pylablib.core.devio.comm\_backend.FT232DeviceBackend attribute), 178  
 Error (pylablib.core.devio.comm\_backend.HIDDeviceBackend attribute), 187  
 Error (pylablib.core.devio.comm\_backend.IDeviceCommBackend attribute), 171  
 Error (pylablib.core.devio.comm\_backend.NetworkDeviceBackend attribute), 181  
 Error (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend attribute), 184  
 Error (pylablib.core.devio.comm\_backend.RecordedDeviceBackend attribute), 189  
 Error (pylablib.core.devio.comm\_backend.SerialDeviceBackend attribute), 176  
 Error (pylablib.core.devio.comm\_backend.VisaDeviceBackend attribute), 173  
 Error (pylablib.core.devio.SCPI.SCPIDevice attribute), 166  
 Error (pylablib.devices.Agilent.pressure.XGS600 attribute), 505  
 Error (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera attribute), 513  
 Error (pylablib.devices.AlliedVision.Bonito.IBonitoCamera attribute), 508  
 Error (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera attribute), 524  
 Error (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera attribute), 537  
 Error (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph attribute), 545  
 Error (pylablib.devices.Arcus.performax.GenericPerformax attribute), 551  
 Error (pylablib.devices.Arcus.performax.Performax2EXStage attribute), 556  
 Error (pylablib.devices.Arcus.performax.Performax4EXStage attribute), 555  
 Error (pylablib.devices.Arcus.performax.PerformaxDMXJSensor attribute), 562  
 Error (pylablib.devices.Arduino.base.IArduinoDevice attribute), 564  
 Error (pylablib.devices.Attocube.anc300.ANC300 attribute), 566  
 Error (pylablib.devices.Attocube.anc350.ANC350 attribute), 570  
 Error (pylablib.devices.AWG.generic.GenericAWG attribute), 455  
 Error (pylablib.devices.AWG.specific.Agilent33220A attribute), 468  
 Error (pylablib.devices.AWG.specific.Agilent33500 attribute), 462  
 Error (pylablib.devices.AWG.specific.InstekAFG2000 attribute), 480  
 Error (pylablib.devices.AWG.specific.InstekAFG2225 attribute), 474  
 Error (pylablib.devices.AWG.specific.RigolDG1000 attribute), 499  
 Error (pylablib.devices.AWG.specific.RSInstekAFG21000 attribute), 486  
 Error (pylablib.devices.AWG.specific.TektronixAFG1000 attribute), 493  
 Error (pylablib.devices.Basler.pylon.BaslerPylonCamera attribute), 578  
 Error (pylablib.devices.BitFlow.BitFlow.BitFlowCamera attribute), 591  
 Error (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber attribute), 585  
 Error (pylablib.devices.Conrad.base.RelayBoard attribute), 597  
 Error (pylablib.devices.Cryocon.base.Cryocon1x attribute), 600  
 Error (pylablib.devices.Cryomagnetics.base.LM500 attribute), 604  
 Error (pylablib.devices.Cryomagnetics.base.LM510 attribute), 608  
 Error (pylablib.devices.DCAM.DCAM.DCAMCamera attribute), 615  
 Error (pylablib.devices.ElektroAutomatik.base.PS2000B attribute), 623  
 Error (pylablib.devices.HighFinesse.wlm.WLM attribute), 626  
 Error (pylablib.devices.Hubner.Cobolt.Cobolt attribute), 630  
 Error (pylablib.devices.IMAQ.IMAQ.IMAQCamera attribute), 641  
 Error (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber attribute), 634  
 Error (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera attribute), 657  
 Error (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera attribute), 651  
 Error (pylablib.devices.interface.camera.IAttributeCamera attribute), 996  
 Error (pylablib.devices.interface.camera.IBinROICamera attribute), 1015  
 Error (pylablib.devices.interface.camera.ICamera attribute), 990  
 Error (pylablib.devices.interface.camera.IExposureCamera attribute), 1006  
 Error (pylablib.devices.interface.camera.IGrabberAttributeCamera attribute), 1001  
 Error (pylablib.devices.interface.camera.IROICamera attribute), 1010  
 Error (pylablib.devices.Keithley.multimeter.Keithley2110 attribute), 1010

- attribute), 666
- Error (pylablib.devices.KJL.base.KJL300 attribute), 663
- Error (pylablib.devices.Lakeshore.base.Lakeshore218 attribute), 672
- Error (pylablib.devices.Lakeshore.base.Lakeshore370 attribute), 678
- Error (pylablib.devices.LaserQuantum.base.Finesse attribute), 683
- Error (pylablib.devices.Leybold.base.GenericITR attribute), 686
- Error (pylablib.devices.Leybold.base.ITR90 attribute), 687
- error (pylablib.devices.Leybold.base.TUpdateValue attribute), 685
- Error (pylablib.devices.LighthousePhotonics.base.SproutG attribute), 690
- Error (pylablib.devices.Lumel.base.LumelRE72Controller attribute), 693
- Error (pylablib.devices.M2.base.ICEBlocDevice attribute), 696
- Error (pylablib.devices.M2.emm.EMM attribute), 699
- Error (pylablib.devices.M2.solstis.Solstis attribute), 705
- Error (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera attribute), 708
- Error (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice attribute), 715
- Error (pylablib.devices.Newport.picomotor.Picomotor8742 attribute), 736
- Error (pylablib.devices.NI.daq.NIDAQ attribute), 718
- Error (pylablib.devices.NKT.interbus.GenericInterbusDevice attribute), 726
- Error (pylablib.devices.NKT.interbus.InterbusSystem attribute), 733
- Error (pylablib.devices.Omron.base.OmronE5xCController attribute), 747
- Error (pylablib.devices.Ophir.base.OphirDevice attribute), 749
- Error (pylablib.devices.Ophir.base.VegaPowerMeter attribute), 753
- Error (pylablib.devices.OZOptics.base.DD100 attribute), 743
- Error (pylablib.devices.OZOptics.base.EPC04 attribute), 744
- Error (pylablib.devices.OZOptics.base.OZOpticsDevice attribute), 740
- Error (pylablib.devices.OZOptics.base.TF100 attribute), 741
- Error (pylablib.devices.PCO.SC2.PCOSC2Camera attribute), 755
- Error (pylablib.devices.Pfeiffer.base.DPG202 attribute), 767
- Error (pylablib.devices.Pfeiffer.base.TPG260 attribute), 764
- Error (pylablib.devices.Photometrics.pvcam.PvcamCamera attribute), 772
- Error (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera attribute), 782
- Error (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera attribute), 805
- Error (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera attribute), 788
- Error (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera attribute), 797
- Error (pylablib.devices.PhysikInstrumente.base.GenericPIController attribute), 814
- Error (pylablib.devices.PhysikInstrumente.base.PIE515 attribute), 819
- Error (pylablib.devices.PhysikInstrumente.base.PIE516 attribute), 817
- Error (pylablib.devices.PrincetonInstruments.picam.PicamCamera attribute), 828
- Error (pylablib.devices.Rigol.power\_supply.DP1116A attribute), 834
- Error (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera attribute), 848
- Error (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber attribute), 841
- Error (pylablib.devices.Sirah.Matisse.SirahMatisse attribute), 856
- Error (pylablib.devices.SmarAct.MCS2.MCS2 attribute), 869
- Error (pylablib.devices.SmarAct.scu3d.SCU3D attribute), 874
- Error (pylablib.devices.Standa.base.Standa8SMC attribute), 878
- Error (pylablib.devices.Tektronix.base.DPO2000 attribute), 895
- Error (pylablib.devices.Tektronix.base.ITektronixScope attribute), 881
- Error (pylablib.devices.Tektronix.base.TDS2000 attribute), 888
- Error (pylablib.devices.Thorlabs.elliptec.ElliptecMotor attribute), 912
- Error (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice attribute), 916
- Error (pylablib.devices.Thorlabs.kinesis.KinesisDevice attribute), 921
- Error (pylablib.devices.Thorlabs.kinesis.KinesisMotor attribute), 932
- Error (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController attribute), 939
- Error (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor attribute), 936
- Error (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector attribute), 943
- Error (pylablib.devices.Thorlabs.kinesis.MFF attribute), 925
- Error (pylablib.devices.Thorlabs.misc.GenericPM attribute), 925

- [attribute](#)), 946
  - Error (pylablib.devices.Thorlabs.misc.PM160 attribute), 950
  - Error (pylablib.devices.Thorlabs.serial.FW attribute), 958
  - Error (pylablib.devices.Thorlabs.serial.FWv1 attribute), 961
  - Error (pylablib.devices.Thorlabs.serial.MDT69xA attribute), 965
  - Error (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface attribute), 954
  - Error (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera attribute), 903
  - Error (pylablib.devices.Toptica.ibeam.TopticaIBeam attribute), 969
  - Error (pylablib.devices.Trinamic.base.TMCM1110 attribute), 972
  - Error (pylablib.devices.Trinamic.base.TMCMx110 attribute), 976
  - Error (pylablib.devices.uc480.uc480.UC480Camera attribute), 1024
  - Error (pylablib.devices.Voltcraft.multimeter.VC7055 attribute), 981
  - Error (pylablib.devices.Voltcraft.multimeter.VC880 attribute), 985
  - Error (pylablib.devices.Windows.joystick.Joystick attribute), 988
  - errors (pylablib.devices.PCO.SC2.TCcameraStatus attribute), 755
  - escape\_string() (in module pylablib.core.utils.string), 450
  - EthernetIMAQdxCamera (class in pylablib.devices.IMAQdx.IMAQdx), 656
  - EthernetIMAQdxCamera.CallbackManager (class in pylablib.devices.IMAQdx.IMAQdx), 657
  - exc\_mode (pylablib.devices.Lakeshore.base.TLakeshore370RangeSettings attribute), 677
  - exc\_range (pylablib.devices.Lakeshore.base.TLakeshore370RangeSettings attribute), 677
  - execute() (pylablib.core.thread.callsync.QScheduledCall method), 332
  - exhaust\_messages() (pylablib.devices.Voltcraft.multimeter.VC880 method), 985
  - exint() (in module pylablib.core.thread.controller), 341
  - exists (pylablib.devices.PrincetonInstruments.picam.Picam attribute), 825
  - exp\_decay\_k() (in module pylablib.core.dataproc.specfunc), 151
  - expand\_relative\_path() (in module pylablib.core.utils.module), 437
  - ExpandedContainerDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 210
  - export\_clock() (pylablib.devices.NI.daq.NIDAQ method), 719
  - exposure (pylablib.devices.Andor.AndorSDK2.TCcycleTimings attribute), 523
  - exposure (pylablib.devices.interface.camera.TAcqTimings attribute), 1005
  - exposure\_ns (pylablib.devices.Photometrics.pvcam.TFrameInfo attribute), 771
  - exsafe() (in module pylablib.core.thread.controller), 341
  - exsafeSlot() (in module pylablib.core.thread.controller), 341
  - ExternalBinTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 207
  - ExternalNumpyDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 209
  - ExternalTextTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 206
  - extract\_escaped\_string() (in module pylablib.core.utils.string), 452
  - extract\_status\_line() (in module pylablib.devices.interface.camera), 1020
- ## F
- f (pylablib.core.utils.files.TempFile attribute), 413
  - fail() (pylablib.core.thread.callsync.QScheduledCall method), 332
  - fail() (pylablib.core.thread.synchronizing.QMultiThreadNotifier method), 368
  - fail\_exec\_point() (pylablib.core.thread.controller.QTaskThread method), 358
  - fail\_exec\_point() (pylablib.core.thread.controller.QThreadController method), 348
  - failed() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330
  - failed() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331
  - fall\_speed (pylablib.devices.Sirah.Matisse.TScanParameters attribute), 856
  - falling (pylablib.devices.Sirah.Matisse.TScanMode attribute), 856
  - fast\_shift\_roi() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 783
  - fast\_shift\_roi() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 806
  - fast\_shift\_roi() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 789
  - fast\_shift\_roi() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 798



FGrabAttribute (class in py-lablib.devices.SiliconSoftware.fgrab), 839  
 file (pylablib.devices.SiliconSoftware.fgrab.TAppletInfo attribute), 839  
 file (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute), 839  
 file\_format (pylablib.core.fileio.dict\_entry.ExternalNumpyDictionaryEntry attribute), 209  
 file\_format (pylablib.core.fileio.dict\_entry.IExternalFileFormat attribute), 208  
 filename (pylablib.core.thread.threadprop.TimeoutThreadError attribute), 369  
 filename (pylablib.core.utils.net.SocketError attribute), 440  
 filename (pylablib.core.utils.net.SocketTimeout attribute), 440  
 filename2 (pylablib.core.thread.threadprop.TimeoutThreadError attribute), 369  
 filename2 (pylablib.core.utils.net.SocketError attribute), 440  
 filename2 (pylablib.core.utils.net.SocketTimeout attribute), 440  
 files (pylablib.core.utils.files.FolderList attribute), 414  
 fill\_voltage\_output\_buffer() (pylablib.devices.NI.daq.NIDAQ method), 722  
 filt (pylablib.core.utils.observer\_pool.ObserverPool.Observer attribute), 445  
 filter\_args\_dict() (pylablib.core.dataproc.callable.FunctionCallable method), 132  
 filter\_args\_dict() (pylablib.core.dataproc.callable.ICallable method), 130  
 filter\_args\_dict() (pylablib.core.dataproc.callable.JoinedCallable method), 131  
 filter\_args\_dict() (pylablib.core.dataproc.callable.MethodCallable method), 133  
 filter\_args\_dict() (pylablib.core.dataproc.callable.MultiplexedCallable method), 131  
 filter\_array\_phase (pylablib.devices.Thorlabs.TLCamera.TColorInfo attribute), 903  
 filter\_by() (in module pylablib.core.dataproc.utils), 163  
 filter\_dict() (in module pylablib.core.utils.general), 426  
 filter\_limiter() (in module pylablib.core.gui.limiter), 308  
 filter\_self() (pylablib.core.utils.dictionary.Dictionary method), 384  
 filter\_self() (pylablib.core.utils.dictionary.DictionaryPointer method), 388  
 filter\_self() (pylablib.core.utils.dictionary.FilterTree method), 405  
 filter\_self() (pylablib.core.utils.dictionary.PrefixTree method), 397  
 filter\_string\_list() (in module pylablib.core.utils.string), 450  
 FilterTree (class in pylablib.core.utils.dictionary), 403  
 finalize\_task() (pylablib.core.thread.controller.QTaskThread method), 353  
 finalized (pylablib.core.thread.controller.QThreadControllerThread attribute), 341  
 find\_all\_first\_locations() (in module pylablib.core.utils.string), 449  
 find\_all\_prefixes() (pylablib.core.utils.dictionary.PrefixTree method), 395  
 find\_by\_serial() (in module pylablib.devices.uc480.uc480), 1023  
 find\_by\_serial() (pylablib.devices.uc480.uc480.UC480Camera static method), 1025  
 find\_closest\_arg() (in module pylablib.core.dataproc.utils), 164  
 find\_closest\_value() (in module pylablib.core.dataproc.utils), 164  
 find\_columns\_lines() (in module pylablib.core.fileio.loadfile\_utils), 216  
 find\_dict\_string() (in module pylablib.core.utils.string), 449  
 find\_discrete\_step() (in module pylablib.core.dataproc.utils), 164  
 find\_first\_entry() (in module pylablib.core.utils.string), 449  
 find\_intersection() (pylablib.core.utils.dictionary.Dictionary static method), 384  
 find\_intersection() (pylablib.core.utils.dictionary.DictionaryPointer static method), 388  
 find\_intersection() (pylablib.core.utils.dictionary.FilterTree static method), 405  
 find\_intersection() (pylablib.core.utils.dictionary.PrefixTree static method), 397  
 find\_largest\_prefix() (pylablib.core.utils.dictionary.PrefixTree method), 394  
 find\_layout\_element() (in module pylablib.core.gui.utils), 309  
 find\_list\_string() (in module pylablib.core.utils.string), 449

<code>find_local_extrema()</code> (in module <code>pylablib.core.dataproc.feature</code> ), 136	<code>firmware_version</code> ( <code>pylablib.devices.Thorlabs.TLCamera.TDeviceInfo</code> attribute), 902
<code>find_observers()</code> ( <code>pylablib.core.utils.observer_pool.ObserverPool</code> method), 446	<code>fit()</code> ( <code>pylablib.core.dataproc.fitting.Fitter</code> method), 142
<code>find_peaks_cutoff()</code> (in module <code>pylablib.core.dataproc.feature</code> ), 135	<code>Fitter</code> (class in <code>pylablib.core.dataproc.fitting</code> ), 141
<code>find_savetime_comment()</code> (in module <code>pylablib.core.fileio.loadfile_utils</code> ), 216	<code>fixed_size</code> ( <code>pylablib.core.utils.ipc.TShmemVarDesc</code> attribute), 436
<code>find_skipped_frames()</code> (in module <code>pylablib.devices.PhotonFocus.PhotonFocus</code> ), 813	<code>flags</code> ( <code>pylablib.devices.IMAQdx.IMAQdx.TCameraInfo</code> attribute), 648
<code>fine_sweep_start()</code> ( <code>pylablib.devices.Sirah.tuner.MatisseTuner</code> method), 867	<code>flags</code> ( <code>pylablib.devices.Photometrics.pvcam.TFrameInfo</code> attribute), 771
<code>fine_sweep_stop()</code> ( <code>pylablib.devices.Sirah.tuner.MatisseTuner</code> method), 867	<code>flags</code> ( <code>pylablib.devices.PrincetonInstruments.picam.TROIConstraints</code> attribute), 824
<code>fine_tune_to()</code> ( <code>pylablib.devices.Sirah.tuner.MatisseTuner</code> method), 866	<code>flags</code> ( <code>pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo</code> attribute), 839
<code>fine_tune_to_gen()</code> ( <code>pylablib.devices.Sirah.tuner.MatisseTuner</code> method), 866	<code>flags</code> ( <code>pylablib.devices.Standa.base.TFullState</code> attribute), 877
<code>fine_tune_wavelength()</code> ( <code>pylablib.devices.M2.emm.EMM</code> method), 698	<code>flags</code> ( <code>pylablib.devices.Thorlabs.misc.TPMSensorInfo</code> attribute), 945
<code>fine_tune_wavelength()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 702	<code>flags</code> ( <code>pylablib.devices.uc480.uc480.TFrameInfo</code> attribute), 1024
<code>Finesse</code> (class in <code>pylablib.devices.LaserQuantum.base</code> ), 683	<code>flatten_list()</code> (in module <code>pylablib.core.utils.general</code> ), 426
<code>finished</code> ( <code>pylablib.core.thread.controller.QTaskThread</code> attribute), 358	<code>flip_byteorder()</code> ( <code>pylablib.core.devio.data_format.DataFormat</code> method), 193
<code>finished</code> ( <code>pylablib.core.thread.controller.QThreadController</code> attribute), 342	<code>flip_fourier_transform()</code> (in module <code>pylablib.core.dataproc.fourier</code> ), 145
<code>finishing()</code> ( <code>pylablib.core.thread.controller.QTaskThread</code> method), 358	<code>float_to_str_SI()</code> (in module <code>pylablib.core.gui.formatter</code> ), 307
<code>finishing()</code> ( <code>pylablib.core.thread.controller.QThreadController</code> method), 348	<code>FloatFormatter</code> (class in <code>pylablib.core.gui.formatter</code> ), 307
<code>firmware</code> ( <code>pylablib.devices.Thorlabs.misc.TPMDeviceInfo</code> attribute), 945	<code>flush()</code> ( <code>pylablib.core.devio.SCPI.SCPIDevice</code> method), 168
<code>firmware_build_date</code> ( <code>pylablib.devices.Hubner.Cobolt.TDeviceInfo</code> attribute), 630	<code>flush()</code> ( <code>pylablib.core.utils.general.StreamFileLogger</code> method), 432
<code>firmware_date</code> ( <code>pylablib.devices.Hubner.Cobolt.TDeviceInfo</code> attribute), 630	<code>flush()</code> ( <code>pylablib.devices.AWG.generic.GenericAWG</code> method), 459
<code>firmware_version</code> ( <code>pylablib.devices.Andor.AndorSDK3.TDeviceInfo</code> attribute), 536	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.Agilent33220A</code> method), 468
<code>firmware_version</code> ( <code>pylablib.devices.Hubner.Cobolt.TDeviceInfo</code> attribute), 630	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.Agilent33500</code> method), 462
<code>firmware_version</code> ( <code>pylablib.devices.SmarAct.scu3d.TDeviceInfo</code> attribute), 874	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2000</code> method), 481
	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2225</code> method), 475
	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.RigolDG1000</code> method), 499
	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.RSInstekAFG21000</code> method), 487
	<code>flush()</code> ( <code>pylablib.devices.AWG.specific.TektronixAFG1000</code> method), 493
	<code>flush()</code> ( <code>pylablib.devices.Basler.pylon.BaslerPylonCamera.BufferManager</code> method), 580

- `flush()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 944
- `flush()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 601
- `flush()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 606
- `flush()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 609
- `flush()` (`pylablib.devices.Keithley.multimeter.Keithley2110` method), 668
- `flush()` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 674
- `flush()` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 679
- `flush()` (`pylablib.devices.M2.base.ICEBlocDevice` method), 696
- `flush()` (`pylablib.devices.M2.emm.EMM` method), 700
- `flush()` (`pylablib.devices.M2.solstis.Solstis` method), 706
- `flush()` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 821
- `flush()` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 835
- `flush()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 861
- `flush()` (`pylablib.devices.Tektronix.base.DPO2000` method), 895
- `flush()` (`pylablib.devices.Tektronix.base.ITektronixScope` method), 885
- `flush()` (`pylablib.devices.Tektronix.base.TDS2000` method), 888
- `flush()` (`pylablib.devices.Thorlabs.misc.GenericPM` method), 947
- `flush()` (`pylablib.devices.Thorlabs.misc.PM160` method), 950
- `flush()` (`pylablib.devices.Thorlabs.serial.FW` method), 958
- `flush()` (`pylablib.devices.Thorlabs.serial.FWv1` method), 962
- `flush()` (`pylablib.devices.Thorlabs.serial.MDT69xA` method), 965
- `flush()` (`pylablib.devices.Thorlabs.serial.ThorlabsSerialIn` method), 955
- `flush()` (`pylablib.devices.Voltcraft.multimeter.VC7055` method), 982
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.BasicKin` method), 917
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.KinesisDevice` method), 922
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.KinesisMotor` method), 932
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezo` method), 939
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor` method), 936
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.KinesisQuadDetect` method), 944
- `flush_comm()` (`pylablib.devices.Thorlabs.kinesis.MFF` method), 925
- `flush_read()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` method), 180
- `flush_read()` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` method), 188
- `flush_read()` (`pylablib.core.devio.comm_backend.IDeviceCommBackend` method), 172
- `flush_read()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` method), 182
- `flush_read()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` method), 185
- `flush_read()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` method), 190
- `flush_read()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` method), 177
- `flush_read()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` method), 174
- `fmt` (`pylablib.devices.Lakeshore.base.TLakeshore218CurveHeader` attribute), 672
- `FmtStringFormatter` (class in `pylablib.core.gui.formatter`), 307
- `focal_length` (`pylablib.devices.Andor.Shamrock.TOpticalParameters` attribute), 544
- `focal_tilt` (`pylablib.devices.Andor.Shamrock.TOpticalParameters` attribute), 545
- `focusInEvent()` (`pylablib.core.gui.widgets.edit.TextEdit` method), 275
- `focusOutEvent()` (`pylablib.core.gui.widgets.edit.TextEdit` method), 275
- `FolderFileSystemDataLocation` (class in `pylablib.core.fileio.location`), 221
- `FolderList` (class in `pylablib.core.utils.files`), 414
- `folders` (`pylablib.core.utils.files.FolderList` attribute), 415
- `follow()` (`pylablib.core.dataproc.ctransform_fallback.CLinear2DTransform` method), 134
- `followed()` (`pylablib.core.dataproc.transform.Indexed2DTransform` method), 162
- `followed()` (`pylablib.core.dataproc.transform.LinearTransform` method), 161
- `forDeviceTrigger()` (`pylablib.devices.Tektronix.base.DPO2000` method), 895
- `force_trigger()` (`pylablib.devices.Tektronix.base.ITektronixScope` method), 883
- `ForControlLogger()` (`pylablib.devices.Tektronix.base.TDS2000` method), 889
- `fourier_filter()` (in module `pylablib.core.dataproc.filters`), 139

fourier\_filter\_bandpass() (in module py-  
 lablib.core.dataproc.filters), 140  
 fourier\_filter\_bandstop() (in module py-  
 lablib.core.dataproc.filters), 140  
 fourier\_make\_response\_real() (in module py-  
 lablib.core.dataproc.filters), 139  
 fourier\_transform() (in module py-  
 lablib.core.dataproc.fourier), 145  
 frame\_index (pylablib.devices.Andor.AndorSDK3.TFrameInfo attribute), 536  
 frame\_index (pylablib.devices.DCAM.DCAM.TFrameInfo attribute), 615  
 frame\_index (pylablib.devices.interface.camera.TFrameInfo attribute), 990  
 frame\_index (pylablib.devices.PCO.SC2.TFrameInfo attribute), 755  
 frame\_index (pylablib.devices.Photometrics.pvcam.TFrameInfo attribute), 771  
 frame\_index (pylablib.devices.PrincetonInstruments.picam.TFrameInfo attribute), 827  
 frame\_index (pylablib.devices.SiliconSoftware.fgrab.TFrameInfo attribute), 841  
 frame\_index (pylablib.devices.Thorlabs.TLCamera.TFrameInfo attribute), 903  
 frame\_index (pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024  
 frame\_period (pylablib.devices.interface.camera.TAcqTime attribute), 1005  
 FrameCounter (class in py-  
 lablib.devices.interface.camera), 994  
 FrameNotifier (class in py-  
 lablib.devices.interface.camera), 995  
 frames\_done (pylablib.devices.Andor.AndorSDK2.TAcqProc attribute), 523  
 frameskip\_events (py-  
 lablib.devices.uc480.uc480.TAcquiredFramesStatus attribute), 1023  
 framestamp (pylablib.devices.AlliedVision.Bonito.TStatusLine attribute), 522  
 framestamp (pylablib.devices.DCAM.DCAM.TFrameInfo attribute), 615  
 framestamp (pylablib.devices.PCO.SC2.TStatusLine attribute), 763  
 framestamp (pylablib.devices.Photometrics.pvcam.TFrameInfo attribute), 771  
 framestamp (pylablib.devices.PrincetonInstruments.picam.TFrameInfo attribute), 827  
 framestamp (pylablib.devices.SiliconSoftware.fgrab.TFrameInfo attribute), 841  
 framestamp (pylablib.devices.Thorlabs.TLCamera.TFrameInfo attribute), 903  
 framestamp (pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024  
 framestamp\_checker (py-  
 lablib.devices.interface.camera.TStatusLineDescription attribute), 1019  
 FrameTransferError (py-  
 lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera attribute), 513  
 FrameTransferError (py-  
 lablib.devices.AlliedVision.Bonito.IBonitoCamera attribute), 509  
 FrameTransferError (py-  
 lablib.devices.Andor.AndorSDK2.AndorSDK2Camera attribute), 530  
 FrameTransferError (py-  
 lablib.devices.Andor.AndorSDK3.AndorSDK3Camera attribute), 537  
 FrameTransferError (py-  
 lablib.devices.Basler.pylon.BaslerPylonCamera attribute), 580  
 FrameTransferError (py-  
 lablib.devices.BitFlow.BitFlow.BitFlowCamera attribute), 591  
 FrameTransferError (py-  
 lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber attribute), 587  
 FrameTransferError (py-  
 lablib.devices.DCAM.DCAM.DCAMCamera attribute), 618  
 FrameTransferError (py-  
 lablib.devices.IMAQ.IMAQ.IMAQCamera attribute), 641  
 FrameTransferError (py-  
 lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber attribute), 637  
 FrameTransferError (py-  
 lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera attribute), 657  
 FrameTransferError (py-  
 lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera attribute), 653  
 FrameTransferError (py-  
 lablib.devices.interface.camera.IAttributeCamera attribute), 996  
 FrameTransferError (py-  
 lablib.devices.interface.camera.IBinROICamera attribute), 1015  
 FrameTransferError (py-  
 lablib.devices.interface.camera.ICamera attribute), 990  
 FrameTransferError (py-  
 lablib.devices.interface.camera.IExposureCamera attribute), 1006  
 FrameTransferError (py-  
 lablib.devices.interface.camera.IGrabberAttributeCamera attribute), 1001  
 FrameTransferError (py-



`lablib.devices.interface.camera.IROICamera` (py-  
`attribute`), 1011  
`FrameTransferError` (py-  
`lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera`  
`attribute`), 710  
`FrameTransferError` (py-  
`lablib.devices.PCO.SC2.PCOSC2Camera`  
`attribute`), 759  
`FrameTransferError` (py-  
`lablib.devices.Photometrics.pvcam.PvcamCamera`  
`attribute`), 775  
`FrameTransferError` (py-  
`lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera`  
`attribute`), 784  
`FrameTransferError` (py-  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera`  
`attribute`), 806  
`FrameTransferError` (py-  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusMADCamera`  
`attribute`), 788  
`FrameTransferError` (py-  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera`  
`attribute`), 798  
`FrameTransferError` (py-  
`lablib.devices.PrincetonInstruments.picam.PicamCamera`  
`attribute`), 830  
`FrameTransferError` (py-  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera`  
`attribute`), 848  
`FrameTransferError` (py-  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera`  
`attribute`), 844  
`FrameTransferError` (py-  
`lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera`  
`attribute`), 907  
`FrameTransferError` (py-  
`lablib.devices.uc480.uc480.UC480Camera`  
`attribute`), 1025  
`freeP` (pylablib.devices.Sirah.Matisse.TSlowpiezoCtlParameters  
`attribute`), 855  
`frequency` (pylablib.devices.SmarAct.MCS2.TStepMoveParams  
`attribute`), 869  
`FrequencyReadSirahError`, 864  
`friendly_name` (pylablib.devices.Basler.pylon.TCameraInfo  
`attribute`), 575  
`friendly_name` (pylablib.devices.Basler.pylon.TDeviceInfo  
`attribute`), 577  
`from_args` (pylablib.core.utils.ipc.IIPCCChannel class  
`method`), 435  
`from_args` (pylablib.core.utils.ipc.PipeIPCCChannel  
`class method`), 435  
`from_args` (pylablib.core.utils.ipc.SharedMemIPCCChannel  
`class method`), 436  
`from_args` (pylablib.core.utils.ipc.SharedMemIPCTable  
`class method`), 437  
`from_array` (pylablib.core.dataproc.table\_wrap.Array1DWrapper  
`static method`), 154  
`from_array` (pylablib.core.dataproc.table\_wrap.Array2DWrapper  
`static method`), 158  
`from_array` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper  
`static method`), 160  
`from_array` (pylablib.core.dataproc.table\_wrap.I1DWrapper  
`static method`), 153  
`from_array` (pylablib.core.dataproc.table\_wrap.I2DWrapper  
`static method`), 156  
`from_array` (pylablib.core.dataproc.table\_wrap.Series1DWrapper  
`static method`), 155  
`from_centersize` (py-  
`lablib.core.dataproc.image.ROI` class method),  
`from_columns` (pylablib.core.dataproc.table\_wrap.Array1DWrapper  
`class method`), 154  
`from_columns` (pylablib.core.dataproc.table\_wrap.Array2DWrapper  
`class method`), 158  
`from_columns` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper  
`class method`), 160  
`from_columns` (pylablib.core.dataproc.table\_wrap.I1DWrapper  
`class method`), 153  
`from_columns` (pylablib.core.dataproc.table\_wrap.I2DWrapper  
`class method`), 156  
`from_columns` (pylablib.core.dataproc.table\_wrap.Series1DWrapper  
`class method`), 155  
`from_data` (in module pylablib.core.fileio.dict\_entry),  
204  
`from_data_obj` (pylablib.core.fileio.dict\_entry.DictEntryBuilder  
`method`), 203  
`from_desc` (pylablib.core.devio.data\_format.DataFormat  
`static method`), 193  
`from_desc_SCPI` (py-  
`lablib.core.devio.data_format.DataFormat`  
`static method`), 193  
`from_dict` (in module pylablib.core.fileio.dict\_entry),  
204  
`from_dict` (pylablib.core.fileio.dict\_entry.DictEntryParser  
`method`), 203  
`from_dict` (pylablib.core.fileio.dict\_entry.ExpandedContainerDictionary  
`class method`), 210  
`from_dict` (pylablib.core.fileio.dict\_entry.ExternalBinTableDictionary  
`class method`), 208  
`from_dict` (pylablib.core.fileio.dict\_entry.ExternalNumpyDictionaryEntry  
`class method`), 209  
`from_dict` (pylablib.core.fileio.dict\_entry.ExternalTextTableDictionary  
`class method`), 207  
`from_dict` (pylablib.core.fileio.dict\_entry.IDictionaryEntry  
`class method`), 204  
`from_dict` (pylablib.core.fileio.dict\_entry.IExternalFileDictionaryEntry  
`class method`), 208  
`from_dict` (pylablib.core.fileio.dict\_entry.IExternalTableDictionaryEntry  
`class method`), 208

class method), 206  
 from\_dict() (pylablib.core.fileio.dict\_entry.InlineTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 206  
 class method), 206  
 from\_dict() (pylablib.core.fileio.dict\_entry.ITableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 205  
 class method), 205  
 from\_function() (pylablib.core.utils.functions.FunctionSignature (class in pylablib.core.utils.functions), 421  
 static method), 421  
 from\_json() (pylablib.core.utils.dictionary.Dictionary (class in pylablib.core.utils.dictionary), 383  
 class method), 383  
 from\_json() (pylablib.core.utils.dictionary.DictionaryPointer (class in pylablib.core.utils.dictionary), 389  
 class method), 389  
 from\_json() (pylablib.core.utils.dictionary.FilterTree (class in pylablib.core.utils.dictionary), 405  
 class method), 405  
 from\_json() (pylablib.core.utils.dictionary.PrefixTree (class in pylablib.core.utils.dictionary), 397  
 class method), 397  
 from\_matr\_shift() (pylablib.core.dataproc.ctransform\_fallback.CLinear2DTransform (class in pylablib.core.dataproc.ctransform\_fallback), 134  
 class method), 134  
 from\_object() (pylablib.core.fileio.location.LocationName (class in pylablib.core.fileio.location), 217  
 static method), 217  
 from\_Pa() (pylablib.devices.Agilent.pressure.XGS600 (class in pylablib.devices.Agilent.pressure), 506  
 method), 506  
 from\_Pa() (pylablib.devices.Pfeiffer.base.TPG260 (class in pylablib.devices.Pfeiffer.base), 765  
 method), 765  
 from\_row\_string() (in module pylablib.core.utils.string), 453  
 from\_string() (in module pylablib.core.utils.string), 452  
 from\_string() (pylablib.core.fileio.location.LocationName (class in pylablib.core.fileio.location), 217  
 static method), 217  
 from\_string\_partial() (in module pylablib.core.utils.string), 453  
 FT232DeviceBackend (class in pylablib.core.devio.comm\_backend), 178  
 full\_exit() (in module pylablib.core.utils.general), 428  
 full\_name (pylablib.core.utils.files.TempFile (class in pylablib.core.utils.files), 413  
 attribute), 413  
 full\_name (pylablib.devices.SiliconSoftware.fgrab.TBoardInfo (class in pylablib.devices.SiliconSoftware.fgrab), 838  
 attribute), 838  
 fullsplit() (in module pylablib.core.utils.files), 413  
 func (pylablib.core.thread.callsync.QScheduledCall.Callback (class in pylablib.core.thread.callsync), 332  
 attribute), 332  
 func (pylablib.devices.Voltcraft.multimeter.TVC880Reading (class in pylablib.devices.Voltcraft.multimeter), 985  
 attribute), 985  
 funcsig() (in module pylablib.core.utils.functions), 422  
 function (pylablib.devices.Keithley.multimeter.TConfigurationParameters (class in pylablib.devices.Keithley.multimeter), 666  
 attribute), 666  
 function (pylablib.devices.Modbus.modbus.TModbusFrame (class in pylablib.devices.Modbus.modbus), 715  
 attribute), 715  
 FunctionCallable (class in pylablib.core.dataproc.callable), 132  
 FunctionCallable.NamesBoundCall (class in pylablib.core.dataproc.callable), 132  
 FunctionParameterClass (class in pylablib.core.devio.interface), 201  
 FunctionSignature (class in pylablib.core.utils.functions), 420  
 FW (class in pylablib.devices.Thorlabs.serial), 957  
 fw\_freq (pylablib.devices.Thorlabs.elliptec.TMotorInfo (class in pylablib.devices.Thorlabs.elliptec), 912  
 attribute), 912  
 fw\_ver (pylablib.devices.Thorlabs.elliptec.TDeviceInfo (class in pylablib.devices.Thorlabs.elliptec), 911  
 attribute), 911  
 fw\_ver (pylablib.devices.Thorlabs.kinesis.TDeviceInfo (class in pylablib.devices.Thorlabs.kinesis), 916  
 attribute), 916  
 FWv1 (class in pylablib.devices.Thorlabs.serial), 961  
 G  
 gain\_idx (pylablib.devices.Photometrics.pvcam.TReadoutInfo (class in pylablib.devices.Photometrics.pvcam), 771  
 attribute), 771  
 gain\_name (pylablib.devices.Photometrics.pvcam.TReadoutInfo (class in pylablib.devices.Photometrics.pvcam), 772  
 attribute), 772  
 gaussian\_filter() (in module pylablib.core.dataproc.filters), 137  
 gaussian\_filter\_nd() (in module pylablib.core.dataproc.filters), 137  
 gaussian\_k() (in module pylablib.core.dataproc.specfunc), 151  
 gcd() (in module pylablib.core.utils.numerical), 444  
 gcd\_approx() (in module pylablib.core.utils.numerical), 444  
 gen\_hamming\_w() (in module pylablib.core.dataproc.specfunc), 151  
 gen\_hamming\_w\_ft() (in module pylablib.core.dataproc.specfunc), 152  
 generate\_indexed\_filename() (in module pylablib.core.utils.files), 412  
 generate\_new\_name() (pylablib.core.fileio.location.FolderFileSystemDataLocation (class in pylablib.core.fileio.location), 222  
 method), 222  
 generate\_new\_name() (pylablib.core.fileio.location.IDataLocation (class in pylablib.core.fileio.location), 218  
 method), 218  
 generate\_new\_name() (pylablib.core.fileio.location.IFileSystemDataLocation (class in pylablib.core.fileio.location), 219  
 method), 219  
 generate\_new\_name() (pylablib.core.fileio.location.OpenedFileLocation (class in pylablib.core.fileio.location), 219  
 method), 219  
 generate\_new\_name() (pylablib.core.fileio.location.PrefixedFileSystemDataLocation (class in pylablib.core.fileio.location), 221  
 method), 221  
 generate\_new\_name() (pylablib.core.fileio.location.SingleFileSystemDataLocation (class in pylablib.core.fileio.location), 220  
 method), 220  
 generate\_prefixed\_filename() (in module pylablib.core.utils.files), 412

[generate\\_temp\\_filename\(\)](#) (in module `pylablib.core.utils.files`), 412  
[GenericAWG](#) (class in `pylablib.devices.AWG.generic`), 455  
[GenericAWGBackendError](#), 455  
[GenericAWGError](#), 455  
[GenericInterbusDevice](#) (class in `pylablib.devices.NKT.interbus`), 725  
[GenericInterbusModule](#) (class in `pylablib.devices.NKT.interbus`), 728  
[GenericITR](#) (class in `pylablib.devices.Leybold.base`), 685  
[GenericKeithleyBackendError](#), 665  
[GenericKeithleyError](#), 665  
[GenericModbusRTUDevice](#) (class in `pylablib.devices.Modbus.modbus`), 715  
[GenericPerformaxStage](#) (class in `pylablib.devices.Arcus.performax`), 551  
[GenericPIController](#) (class in `pylablib.devices.PhysikInstrumente.base`), 814  
[GenericPM](#) (class in `pylablib.devices.Thorlabs.misc`), 946  
[GenericRigolBackendError](#), 834  
[GenericRigolError](#), 833  
[GenericSirahBackendError](#), 864  
[GenericSirahError](#), 864  
[GenericVotcraftBackendError](#), 980  
[GenericVotcraftError](#), 980  
[get\(\)](#) (`pylablib.core.dataproc.filters.RunningDebounceFilter` method), 140  
[get\(\)](#) (`pylablib.core.dataproc.filters.RunningDecimationFilter` method), 140  
[get\(\)](#) (`pylablib.core.fileio.datafile.DataFile` method), 203  
[get\(\)](#) (`pylablib.core.utils.dictionary.Dictionary` method), 378  
[get\(\)](#) (`pylablib.core.utils.dictionary.DictionaryPointer` method), 389  
[get\(\)](#) (`pylablib.core.utils.dictionary.FilterTree` method), 406  
[get\(\)](#) (`pylablib.core.utils.dictionary.ItemAccessor` method), 412  
[get\(\)](#) (`pylablib.core.utils.dictionary.PrefixTree` method), 398  
[get\(\)](#) (`pylablib.core.utils.functions.AttrObjectProperty` method), 424  
[get\(\)](#) (`pylablib.core.utils.functions.IObjectProperty` method), 423  
[get\(\)](#) (`pylablib.core.utils.functions.MethodObjectProperty` method), 424  
[get\\_acceleration\\_factor\(\)](#) (`pylablib.devices.Trinamic.base.TMCM1110` method), 975  
[get\\_acceleration\\_factor\(\)](#) (`pylablib.devices.Trinamic.base.TMCMx110` method), 976  
[get\\_accessory\\_state\(\)](#) (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 548  
[get\\_accum\\_mode\\_parameters\(\)](#) (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 527  
[get\\_acquired\\_frame\\_status\(\)](#) (`pylablib.devices.uc480.uc480.UC480Camera` method), 1027  
[get\\_acquisition\\_mode\(\)](#) (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 527  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera` method), 514  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` method), 510  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 530  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera` method), 540  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.Basler.pylon.BaslerPylonCamera` method), 581  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera` method), 591  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber` method), 587  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.DCAM.DCAM.DCAMCamera` method), 618  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.IMAQ.IMAQ.IMAQCamera` method), 642  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` method), 638  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera` method), 658  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera` method), 653  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.interface.camera.IAttributeCamera` method), 997  
[get\\_acquisition\\_parameters\(\)](#) (`pylablib.devices.interface.camera.IAttributeCamera` method), 997

<code>lablib.devices.interface.camera.IBinROICamera</code> <code>method</code> ), 1015	<code>lablib.devices.HighFinesse.wlm.WLM</code> <code>method</code> ), 627
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.interface.camera.ICamera</code> <code>method</code> ), 990	<code>get_addr()</code> ( <code>pylablib.devices.Newport.picomotor.Picomotor8742</code> <code>method</code> ), 737
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.interface.camera.IExposureCamera</code> <code>method</code> ), 1006	<code>get_addr_map()</code> ( <code>pylablib.devices.Newport.picomotor.Picomotor8742</code> <code>method</code> ), 737
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.interface.camera.IGrabberAttributeCamera</code> <code>method</code> ), 1002	<code>get_all_amp_modes()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 525
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.interface.camera.IROICamera</code> <code>method</code> ), 1011	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> <code>method</code> ), 537
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.Mightex.MightexSSeries.MightexSSGrabber</code> <code>method</code> ), 710	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.Basler.pylon.BaslerPylonCamera</code> <code>method</code> ), 578
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> <code>method</code> ), 759	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 616
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 775	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</code> <code>method</code> ), 658
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 784	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</code> <code>method</code> ), 651
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> <code>method</code> ), 807	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.interface.camera.IAttributeCamera</code> <code>method</code> ), 996
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</code> <code>method</code> ), 789	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 772
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> <code>method</code> ), 798	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 782
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> <code>method</code> ), 830	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> <code>method</code> ), 807
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareGrabber</code> <code>method</code> ), 849	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</code> <code>method</code> ), 790
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareGrabber</code> <code>method</code> ), 844	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> <code>method</code> ), 798
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> <code>method</code> ), 907	<code>get_all_attribute_values()</code> ( <code>py-</code> <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> <code>method</code> ), 828
<code>get_acquisition_parameters()</code> ( <code>py-</code> <code>lablib.devices.uc480.uc480.UC480Camera</code> <code>method</code> ), 1028	<code>get_all_attributes()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> <code>method</code> ), 540
<code>get_acquisition_progress()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 530	<code>get_all_attributes()</code> ( <code>py-</code> <code>lablib.devices.Basler.pylon.BaslerPylonCamera</code> <code>method</code> ), 581
<code>get_active_channel()</code> ( <code>py-</code>	<code>get_all_attributes()</code> ( <code>py-</code> <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 618



[get\\_all\\_attributes\(\)](#) (py- [method](#)), 922  
[lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxGenericGrabber](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Thorlabs.kinesis.KinesisMotor [method](#)), 658  
[get\\_all\\_attributes\(\)](#) (py- [get\\_all\\_axes\(\)](#) (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController [method](#)), 653  
[lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor [method](#)), 939  
[get\\_all\\_attributes\(\)](#) (py- [method](#)), 936  
[lablib.devices.interface.camera.IAttributeCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Thorlabs.kinesis.MFF [method](#)), 996  
[get\\_all\\_attributes\(\)](#) (py- [get\\_all\\_axes\(\)](#) (pylablib.devices.Trinamic.base.TMCMx110 [method](#)), 775  
[lablib.devices.Photometrics.pvcam.PvcamCamera](#) [get\\_all\\_channels\(\)](#) (py- [method](#)), 921  
[get\\_all\\_attributes\(\)](#) (py- [lablib.devices.Thorlabs.kinesis.KinesisDevice](#) [method](#)), 784  
[lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera](#) [get\\_all\\_channels\(\)](#) (py- [method](#)), 807  
[get\\_all\\_attributes\(\)](#) (py- [lablib.devices.Thorlabs.kinesis.KinesisMotor](#) [method](#)), 807  
[lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera](#) [get\\_all\\_channels\(\)](#) (py- [method](#)), 790  
[get\\_all\\_attributes\(\)](#) (py- [lablib.devices.Thorlabs.kinesis.KinesisPiezoController](#) [method](#)), 790  
[lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera](#) [get\\_all\\_channels\(\)](#) (py- [method](#)), 798  
[get\\_all\\_attributes\(\)](#) (py- [lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor](#) [method](#)), 798  
[lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera](#) [get\\_all\\_channels\(\)](#) (py- [method](#)), 830  
[get\\_all\\_attributes\(\)](#) (py- [lablib.devices.Thorlabs.kinesis.MFF](#) [method](#)), 830  
[lablib.devices.PrincetonInstruments.picam.PicamCamera](#) [get\\_all\\_color\\_modes\(\)](#) (py- [method](#)), 552  
[get\\_all\\_axes\(\)](#) (pylablib.devices.Arcus.performax.GenericPerformanceStage [method](#)), 1026  
[get\\_all\\_axes\(\)](#) (pylablib.devices.Arcus.performax.Performax2EXGrabber [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 557  
[lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Arcus.performax.Performax4EXStage [method](#)), 514  
[get\\_all\\_axes\(\)](#) (pylablib.devices.Arcus.performax.PerformaxDMXStage [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 562  
[lablib.devices.IMAQ.IMAQ.IMAQCamera](#) [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 642  
[get\\_all\\_axes\(\)](#) (pylablib.devices.Attocube.anc300.ANC300 [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 569  
[lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Attocube.anc350.ANC350 [method](#)), 634  
[get\\_all\\_axes\(\)](#) (pylablib.devices.interface.stage.IMultiaxisStage [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 1021  
[lablib.devices.interface.camera.IGrabberAttributeCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Newport.picomotor.Picomotor4 [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 738  
[lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.PhysikInstrumente.base.GenericPiezoPiezo [method](#)), 815  
[get\\_all\\_axes\(\)](#) (pylablib.devices.PhysikInstrumente.base.PIE515 [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 821  
[lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.PhysikInstrumente.base.PIE515 [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 818  
[get\\_all\\_axes\(\)](#) (pylablib.devices.SmarAct.MCS2.MCS2 [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 849  
[lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.SmarAct.scu3d.SCUD [get\\_all\\_grabber\\_attribute\\_values\(\)](#) (py- [method](#)), 875  
[lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber](#) [get\\_all\\_axes\(\)](#) (pylablib.devices.Thorlabs.kinesis.KinesisGenericGrabber [get\\_all\\_grabber\\_attributes\(\)](#) (py- [method](#)), 842

`lablib.devices.interface.camera.IGrabberAttributeCamera` `lablib.core.gui.utils`), 309  
`method`), 1001 `get_all_local_addr()` (in module `py-`  
`get_all_grabber_attributes()` (py- `lablib.core.utils.net`), 441  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocus.SILModule_registers()` (py-  
`method`), 799 `lablib.devices.NKT.interbus.InterbusSystem`  
`get_all_grabber_attributes()` (py- `method`), 733  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftware.Callapressures()` (py-  
`method`), 849 `lablib.devices.Agilent.pressure.XGS600`  
`get_all_grabber_attributes()` (py- `method`), 506  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftware.FractalGrabberProperties()` (py-  
`method`), 844 `lablib.devices.SmarAct.MCS2.MCS2` `method`),  
`get_all_handles()` (py- 869  
`lablib.devices.Basler.pylon.BaslerPylonCamera.BaslerPylonCamera.readout_modes()` (py-  
`method`), 579 `lablib.devices.Photometrics.pvcam.PvcamCamera`  
`get_all_indicators()` (py- `method`), 773  
`lablib.core.gui.value_handling.GUIValues` `get_all_readout_speeds()` (py-  
`method`), 329 `lablib.devices.DCAM.DCAM.DCAMCamera`  
`get_all_indicators()` (py- `method`), 616  
`lablib.core.gui.widgets.container.IQContainer` `get_all_registers()` (py-  
`method`), 238 `lablib.devices.NKT.interbus.GenericInterbusModule`  
`get_all_indicators()` (py- `method`), 728  
`lablib.core.gui.widgets.container.IQWidgetContainer` `get_all_registers()` (py-  
`method`), 243 `lablib.devices.NKT.interbus.IInterbusModule`  
`get_all_indicators()` (py- `method`), 727  
`lablib.core.gui.widgets.container.QContainer` `get_all_registers()` (py-  
`method`), 239 `lablib.devices.NKT.interbus.SuperKExtremeInterbusModule`  
`get_all_indicators()` (py- `method`), 729  
`lablib.core.gui.widgets.container.QDialogContainer` `get_all_registers()` (py-  
`method`), 257 `lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule`  
`get_all_indicators()` (py- `method`), 730  
`lablib.core.gui.widgets.container.QFrameContainer` `get_all_registers()` (py-  
`method`), 252 `lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule`  
`get_all_indicators()` (py- `method`), 731  
`lablib.core.gui.widgets.container.QGroupBoxContainer` `get_all_registers()` (py-  
`method`), 262 `lablib.devices.NKT.interbus.SuperKSelectInterbusModule`  
`get_all_indicators()` (py- `method`), 732  
`lablib.core.gui.widgets.container.QScrollAreaContainer` `get_all_relays()` (py-  
`method`), 270 `lablib.devices.Conrad.base.RelayBoard`  
`get_all_indicators()` (py- `method`), 598  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QRemoteWidget()` (in module `py-`  
`method`), 266 `lablib.core.utils.net`), 441  
`get_all_indicators()` (py- `get_all_sensor_kinds()` (py-  
`lablib.core.gui.widgets.container.QTabContainer` `lablib.devices.Cryocon.base.Cryocon1x`  
`method`), 273 `method`), 600  
`get_all_indicators()` (py- `get_all_sensor_readings()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer` `lablib.devices.Cryocon.base.Cryocon1x`  
`method`), 248 `method`), 600  
`get_all_indicators()` (py- `get_all_sensor_readings()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable` `lablib.devices.Lakeshore.base.Lakeshore218`  
`method`), 292 `method`), 673  
`get_all_indicators()` (py- `get_all_temperatures()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable` `lablib.devices.Cryocon.base.Cryocon1x`  
`method`), 303 `method`), 600  
`get_all_layout_containers()` (in module `py-` `get_all_temperatures()` (py-

`lablib.devices.Lakeshore.base.Lakeshore218`  
`method`), 673  
`get_all_trigger_modes()` (py-  
`lablib.devices.DCAM.DCAM.DCAMCamera`  
`method`), 616  
`get_all_values()` (py-  
`lablib.core.gui.value_handling.GUIValues`  
`method`), 328  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.IQContainer`  
`method`), 238  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.IQWidgetContainer`  
`method`), 243  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QContainer`  
`method`), 239  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QDialogContainer`  
`method`), 257  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QFrameContainer`  
`method`), 252  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QGroupBoxContainer`  
`method`), 262  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer`  
`method`), 270  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaWidget`  
`method`), 266  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QTabContainer`  
`method`), 273  
`get_all_values()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer`  
`method`), 248  
`get_all_values()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable`  
`method`), 291  
`get_all_values()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable`  
`method`), 303  
`get_all_vsspeeds()` (py-  
`lablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`method`), 525  
`get_amp_mode()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera)  
`method`), 525  
`get_amplitude()` (py-  
`lablib.devices.AWG.generic.GenericAWG`  
`method`), 456  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.Agilent33220A`  
`method`), 468  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.Agilent33500`  
`method`), 462  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.InstekAFG2000`  
`method`), 481  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.InstekAFG2225`  
`method`), 474  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.RigolDG1000`  
`method`), 499  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.RSInstekAFG21000`  
`method`), 486  
`get_amplitude()` (py-  
`lablib.devices.AWG.specific.TektronixAFG1000`  
`method`), 493  
`get_analog_input()` (py-  
`lablib.devices.Arcus.performax.Performax2EXStage`  
`method`), 557  
`get_analog_input()` (py-  
`lablib.devices.Arcus.performax.Performax4EXStage`  
`method`), 555  
`get_analog_modulation_impedance()` (py-  
`lablib.devices.Hubner.Cobolt.Cobolt` `method`),  
632  
`get_analog_output()` (py-  
`lablib.devices.Lakeshore.base.Lakeshore218`  
`method`), 678  
`get_analog_output()` (py-  
`lablib.devices.Lakeshore.base.Lakeshore370`  
`method`), 678  
`get_analog_output_settings()` (py-  
`lablib.devices.Lakeshore.base.Lakeshore218`  
`method`), 673  
`get_analog_output_settings()` (py-  
`lablib.devices.Lakeshore.base.Lakeshore370`  
`method`), 678  
`get_app()` (in module `pylablib.core.thread.threadprop`),  
370  
`get_appdata_folder()` (in module `py-`  
`lablib.devices.utils.load_lib`), 1032  
`get_appended()` (pylablib.core.dataproc.table\_wrap.Array1DWrapper  
`method`), 154  
`get_appended()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper.Co  
`method`), 157  
`get_appended()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper.Ro  
`method`), 157  
`get_appended()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapp  
`method`), 160  
`get_appended()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapp  
`method`), 159

[get\\_appended\(\)](#) (pylablib.core.dataproc.table\_wrap.Series1DWrapper static method), 861  
[get\\_appended\(\)](#) (pylablib.core.dataproc.table\_wrap.Series1DWrapper method), 155  
[get\\_applet\\_info\(\)](#) (in module py-lablib.devices.SiliconSoftware.fgrab), 839  
[get\\_arg\\_default\(\)](#) (py-lablib.core.dataproc.callable.FunctionCallable method), 132  
[get\\_arg\\_default\(\)](#) (py-lablib.core.dataproc.callable.ICallable method), 130  
[get\\_arg\\_default\(\)](#) (py-lablib.core.dataproc.callable.JoinedCallable method), 131  
[get\\_arg\\_default\(\)](#) (py-lablib.core.dataproc.callable.MethodCallable method), 133  
[get\\_arg\\_default\(\)](#) (py-lablib.core.dataproc.callable.MultiplexedCallable method), 130  
[get\\_arg\\_type\(\)](#) (pylablib.core.devio.SCPI.SCPIDevice static method), 167  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.generic.GenericAWG static method), 459  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.Agilent33220A static method), 469  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.Agilent33500 static method), 462  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.InstekAFG6200 static method), 481  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.InstekAFG2225 static method), 475  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.RigolDG1000 static method), 499  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.RSInstekAFG2100 static method), 487  
[get\\_arg\\_type\(\)](#) (pylablib.devices.AWG.specific.TektronixAFG1000 static method), 493  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Cryocon.base.Cryocon1x static method), 601  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Cryomagnetics.base.LM500 static method), 606  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Cryomagnetics.base.LM510 static method), 609  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Keithley.multimeter.Keithley2110 static method), 668  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Lakeshore.base.Lakeshore218 static method), 674  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Lakeshore.base.Lakeshore370 static method), 679  
[get\\_arg\\_type\(\)](#) (pylablib.devices.PhysikInstrumente.base.PIE515 static method), 821  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Rigol.power\_supply.DP416 static method), 835  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Sirah.Matisse.SirahMatisse static method), 861  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Tektronix.base.DPO2000 static method), 895  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Tektronix.base.ITektronixScope static method), 885  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Tektronix.base.TDS2000 static method), 889  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.misc.GenericPM static method), 947  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.misc.PM160 static method), 950  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.serial.FW static method), 958  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.serial.FWv1 static method), 962  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.serial.MDT69xA static method), 965  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface static method), 955  
[get\\_arg\\_type\(\)](#) (pylablib.devices.Voltcraft.multimeter.VC7055 static method), 982  
[get\\_attenuation\(\)](#) (py-lablib.devices.OZOptics.base.DD100 method), 743  
[get\\_attribute\(\)](#) (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 537  
[get\\_attribute\(\)](#) (py-lablib.devices.Basler.pylon.BaslerPylonCamera method), 581  
[get\\_attribute\(\)](#) (py-lablib.devices.DCAM.DCAM.DCAMCamera method), 618  
[get\\_attribute\(\)](#) (py-lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 658  
[get\\_attribute\(\)](#) (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 653  
[get\\_attribute\(\)](#) (py-lablib.devices.interface.camera.IAttributeCamera method), 996  
[get\\_attribute\(\)](#) (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 775  
[get\\_attribute\(\)](#) (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 784  
[get\\_attribute\(\)](#) (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 807  
[get\\_attribute\(\)](#) (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 790



get_attribute() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 799	(py- get_available_camlink_pixel_formats() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 843	(py-
get_attribute() lablib.devices.PrincetonInstruments.picam.PicamCamera method), 830	(py- get_available_pixel_rates() lablib.devices.PCO.SC2.PCOSC2Camera method), 757	(py-
get_attribute_range() lablib.devices.Photometrics.pvcam.PvcamCamera method), 772	(py- get_available_pixel_rates() lablib.devices.uc480.uc480.UC480Camera method), 1025	(py-
get_attribute_value() lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 537	(py- get_averaging_parameters() lablib.devices.Keithley.multimeter.Keithley2110 method), 668	(py-
get_attribute_value() lablib.devices.Basler.pylon.BaslerPylonCamera method), 578	(pylablib.devices.Windows.joystick.Joystick method), 988	
get_attribute_value() lablib.devices.DCAM.DCAM.DCAMCamera method), 615	get_axis_correction() lablib.devices.Attocube.anc300.ANC300 method), 568	(py-
get_attribute_value() lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 658	get_axis_dir() (pylablib.devices.SmarAct.scu3d.SC3D method), 874	
get_attribute_value() lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 651	get_axis_parameter() lablib.devices.PhysikInstrumente.base.GenericPIController method), 815	(py-
get_attribute_value() lablib.devices.interface.camera.IAttributeCamera method), 996	get_axis_parameter() lablib.devices.PhysikInstrumente.base.PIE516 method), 818	(py-
get_attribute_value() lablib.devices.Photometrics.pvcam.PvcamCamera method), 772	get_axis_parameter() lablib.devices.Trinamic.base.TMCM1110 method), 972	(py-
get_attribute_value() lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 782	get_axis_parameter() lablib.devices.Trinamic.base.TMCMx110 method), 976	(py-
get_attribute_value() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 807	get_axis_serial() lablib.devices.Attocube.anc300.ANC300 method), 566	(py-
get_attribute_value() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 790	get_axis_speed() lablib.devices.Arcus.performax.Performax2EXStage method), 557	(py-
get_attribute_value() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 799	get_axis_speed() lablib.devices.Arcus.performax.Performax4EXStage method), 554	(py-
get_attribute_value() lablib.devices.PrincetonInstruments.picam.PicamCamera method), 828	get_axis_speed() lablib.devices.Arcus.performax.PerformaxDMXJSASage method), 561	(py-
get_autocalibration_parameters() lablib.devices.HighFinesse.wlm.WLM method), 628	get_backend_name() lablib.core.devio.comm_backend.FT232DeviceBackend class method), 180	(py-
get_available_camlink_pixel_formats() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 799	get_backend_name() lablib.core.devio.comm_backend.HIDDeviceBackend class method), 188	(py-
get_available_camlink_pixel_formats() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 849	get_backend_name() lablib.core.devio.comm_backend.IDeviceCommBackend class method), 171	(py-
	get_backend_name() lablib.core.devio.comm_backend.NetworkDeviceBackend class method), 171	(py-

*class method*), 183  
 get\_backend\_name() (py-lablib.core.devio.comm\_backend.PyUSBDeviceBackend *class method*), 185  
 get\_backend\_name() (py-lablib.core.devio.comm\_backend.RecordedDeviceBackend *class method*), 190  
 get\_backend\_name() (py-lablib.core.devio.comm\_backend.SerialDeviceBackend *class method*), 177  
 get\_backend\_name() (py-lablib.core.devio.comm\_backend.VisaDeviceBackend *class method*), 174  
 get\_baseline\_simple() (in module py-lablib.core.dataproc.feature), 135  
 get\_baseplate\_temperature() (py-lablib.devices.Hubner.Cobolt.Cobolt *method*), 630  
 get\_battery\_condition() (py-lablib.devices.Ophir.base.VegaPowerMeter *method*), 752  
 get\_baudrate() (pylablib.devices.Arcus.performax.Performax2EMV *method*), 557  
 get\_baudrate() (pylablib.devices.Arcus.performax.Performax4EX *method*), 553  
 get\_baudrate() (pylablib.devices.Ophir.base.VegaPowerMeter *method*), 752  
 get\_baudrate() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera *method*), 782  
 get\_baudrate() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera *method*), 807  
 get\_baudrate() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera *method*), 790  
 get\_baudrate() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera *method*), 799  
 get\_best\_fit() (in module py-lablib.core.dataproc.fitting), 144  
 get\_binning() (pylablib.devices.uc480.uc480.UC480Camera *method*), 1027  
 get\_bit\_alignment() (py-lablib.devices.PCO.SC2.PCOSC2Camera *method*), 759  
 get\_black\_level() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera *method*), 906  
 get\_black\_level\_offset() (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera *method*), 515  
 get\_black\_level\_offset() (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera *method*), 509  
 get\_black\_level\_offset() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera *method*), 784  
 get\_black\_level\_offset() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera *method*), 807  
 get\_black\_level\_offset() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera *method*), 790  
 get\_black\_level\_offset() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera *method*), 799  
 get\_black\_level\_range() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera *method*), 906  
 get\_board\_info() (in module py-lablib.devices.SiliconSoftware.fgrab), 838  
 get\_boards\_number() (in module py-lablib.devices.SiliconSoftware.fgrab), 838  
 get\_buffer() (pylablib.devices.Basler.pylon.BaslerPylonCamera.BufferManager *method*), 579  
 get\_buffer\_ptr() (py-lablib.devices.PCO.SC2.PCOSC2Camera.BufferManager *method*), 757  
 get\_buffer\_size() (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 530  
 get\_buffer\_size() (pylablib.devices.NI.daq.NIDAQ *method*), 721  
 get\_burst\_mode() (py-lablib.devices.AWG.generic.GenericAWG *method*), 457  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.Agilent33220A *method*), 462  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.Agilent33500 *method*), 462  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.InstekAFG2000 *method*), 481  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.InstekAFG2225 *method*), 475  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.RigolDG1000 *method*), 499  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 487  
 get\_burst\_mode() (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 493  
 get\_burst\_ncycles() (py-lablib.devices.AWG.generic.GenericAWG *method*), 458  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.Agilent33220A *method*), 462  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.Agilent33500 *method*), 462  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.InstekAFG2000 *method*), 481  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.InstekAFG2225 *method*), 475  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.RigolDG1000 *method*), 499  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 487  
 get\_burst\_ncycles() (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 493

- lablib.devices.AWG.specific.Agilent33220A* method), 469
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.Agilent33500*  
method), 463
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.InstekAFG2000*  
method), 481
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.InstekAFG2225*  
method), 475
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.RigolDG1000*  
method), 499
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.RSInstekAFG21000*  
method), 487
- get\_burst\_ncycles()* (py-  
*lablib.devices.AWG.specific.TektronixAFG1000*  
method), 493
- get\_buttons()* (*pylablib.devices.Windows.joystick.Joystick*  
method), 988
- get\_calibration()* (py-  
*lablib.devices.Andor.Shamrock.ShamrockSpectrograph*  
method), 548
- get\_calibration\_factor()* (py-  
*lablib.devices.Pfeiffer.base.TPG260* method),  
765
- get\_callback\_ptr()* (py-  
*lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera*  
method), 657
- get\_callback\_ptr()* (py-  
*lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera*  
method), 652
- get\_camera\_id()* (py-  
*lablib.devices.uc480.uc480.UC480Camera*  
method), 1025
- get\_camera\_status()* (py-  
*lablib.devices.PCO.SC2.PCOSC2Camera*  
method), 756
- get\_cameras\_number()* (in module py-  
*lablib.devices.Andor.AndorSDK2*), 523
- get\_cameras\_number()* (in module py-  
*lablib.devices.Andor.AndorSDK3*), 534
- get\_cameras\_number()* (in module py-  
*lablib.devices.Basler.pylon*), 575
- get\_cameras\_number()* (in module py-  
*lablib.devices.BitFlow.BitFlow*), 585
- get\_cameras\_number()* (in module py-  
*lablib.devices.DCAM.DCAM*), 613
- get\_cameras\_number()* (in module py-  
*lablib.devices.IMAQ.IMAQ*), 633
- get\_cameras\_number()* (in module py-  
*lablib.devices.IMAQdx.IMAQdx*), 649
- get\_cameras\_number()* (in module py-  
*lablib.devices.Mightex.MightexSSeries*),  
708
- get\_cameras\_number()* (in module py-  
*lablib.devices.PCO.SC2*), 754
- get\_cameras\_number()* (in module py-  
*lablib.devices.Photometrics.pvcam*), 769
- get\_cameras\_number()* (in module py-  
*lablib.devices.PhotonFocus.PhotonFocus*),  
780
- get\_cameras\_number()* (in module py-  
*lablib.devices.PrincetonInstruments.picam*),  
824
- get\_cameras\_number()* (in module py-  
*lablib.devices.Thorlabs.TLCamera*), 902
- get\_cameras\_number()* (in module py-  
*lablib.devices.uc480.uc480*), 1023
- get\_camlink\_pixel\_format()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera*  
method), 799
- get\_camlink\_pixel\_format()* (py-  
*lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera*  
method), 849
- get\_camlink\_pixel\_format()* (py-  
*lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber*  
method), 843
- get\_cap\_function\_parameters()* (py-  
*lablib.devices.Keithley.multimeter.Keithley2110*  
method), 667
- get\_capacitance()* (py-  
*lablib.devices.Andor.AndorSDK2.AndorSDK2Camera*  
method), 524
- get\_capacitance()* (py-  
*lablib.devices.PCO.SC2.PCOSC2Camera*  
method), 756
- get\_capacitance()* (py-  
*lablib.devices.Attocube.anc300.ANC300*  
method), 567
- get\_capacitance()* (py-  
*lablib.devices.Attocube.anc350.ANC350*  
method), 572
- get\_channel()* (*pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera*  
method), 525
- get\_channel()* (*pylablib.devices.Cryomagnetics.base.LM500*  
method), 604
- get\_channel()* (*pylablib.devices.Cryomagnetics.base.LM510*  
method), 609
- get\_channel()* (*pylablib.devices.Lakeshore.base.Lakeshore370*  
method), 678
- get\_channel\_bitdepth()* (py-  
*lablib.devices.Andor.AndorSDK2.AndorSDK2Camera*  
method), 525
- get\_channel\_power()* (py-  
*lablib.devices.Toptica.ibeam.TopticaIBeam*

- method*), 969
- `get_channel_range_settings()` (pylablib.devices.Lakeshore.base.Lakeshore370 *method*), 678
- `get_channel_status()` (pylablib.devices.Pfeiffer.base.TPG260 *method*), 765
- `get_channels()` (pylablib.devices.Tektronix.base.DPO2000 *method*), 896
- `get_channels()` (pylablib.devices.Tektronix.base.ITektronixScope *method*), 881
- `get_channels()` (pylablib.devices.Tektronix.base.TDS2000 *method*), 889
- `get_channels_number()` (pylablib.devices.AWG.generic.GenericAWG *method*), 455
- `get_channels_number()` (pylablib.devices.AWG.specific.Agilent33220A *method*), 469
- `get_channels_number()` (pylablib.devices.AWG.specific.Agilent33500 *method*), 463
- `get_channels_number()` (pylablib.devices.AWG.specific.InstekAFG2000 *method*), 481
- `get_channels_number()` (pylablib.devices.AWG.specific.InstekAFG2225 *method*), 475
- `get_channels_number()` (pylablib.devices.AWG.specific.RigolDG1000 *method*), 499
- `get_channels_number()` (pylablib.devices.AWG.specific.RSInstekAFG21000 *method*), 487
- `get_channels_number()` (pylablib.devices.AWG.specific.TektronixAFG1000 *method*), 493
- `get_channels_number()` (pylablib.devices.HighFinesse.wlm.WLM *method*), 627
- `get_channels_number()` (pylablib.devices.Tektronix.base.DPO2000 *method*), 896
- `get_channels_number()` (pylablib.devices.Tektronix.base.ITektronixScope *method*), 881
- `get_channels_number()` (pylablib.devices.Tektronix.base.TDS2000 *method*), 889
- `get_channels_number()` (pylablib.devices.Toptica.ibeam.TopicalIBeam *method*), 969
- `get_child()` (pylablib.core.gui.widgets.container.IQContainer *method*), 237
- `get_child()` (pylablib.core.gui.widgets.container.IQWidgetContainer *method*), 243
- `get_child()` (pylablib.core.gui.widgets.container.QContainer *method*), 239
- `get_child()` (pylablib.core.gui.widgets.container.QDialogContainer *method*), 257
- `get_child()` (pylablib.core.gui.widgets.container.QFrameContainer *method*), 252
- `get_child()` (pylablib.core.gui.widgets.container.QGroupBoxContainer *method*), 262
- `get_child()` (pylablib.core.gui.widgets.container.QScrollAreaContainer *method*), 270
- `get_child()` (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainer *method*), 266
- `get_child()` (pylablib.core.gui.widgets.container.QTabContainer *method*), 273
- `get_child()` (pylablib.core.gui.widgets.container.QWidgetContainer *method*), 248
- `get_child()` (pylablib.core.gui.widgets.param\_table.ParamTable *method*), 292
- `get_child()` (pylablib.core.gui.widgets.param\_table.StatusTable *method*), 303
- `get_cl_move_parameters()` (pylablib.devices.SmarAct.MCS2.MCS2 *method*), 870
- `get_clear_cycles()` (pylablib.devices.Photometrics.pvcam.PvcamCamera *method*), 774
- `get_clear_mode()` (pylablib.devices.Photometrics.pvcam.PvcamCamera *method*), 774
- `get_clearing_time()` (pylablib.devices.Photometrics.pvcam.PvcamCamera *method*), 774
- `get_clock_parameters()` (pylablib.devices.NI.daq.NIDAQ *method*), 719
- `get_clock_period_input_parameters()` (pylablib.devices.NI.daq.NIDAQ *method*), 720
- `get_coarse_tuning_status()` (pylablib.devices.M2.solstis.Solstis *method*), 702
- `get_coarse_wavelength()` (pylablib.devices.M2.solstis.Solstis *method*), 702
- `get_color_format()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera *method*), 904
- `get_color_info()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera *method*), 904
- `get_color_mode()` (pylablib.devices.uc480.uc480.UC480Camera *method*), 1026
- `get_column_index()` (py-





<i>lablib.devices.Trinamic.base.TMCM1110</i> <i>method</i> ), 975	<i>method</i> ), 997	
<i>get_current_speed()</i> ( <i>py-</i> <i>lablib.devices.Trinamic.base.TMCMx110</i> <i>method</i> ), 977	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1015	
<i>get_cursor_order()</i> ( <i>py-</i> <i>lablib.core.gui.widgets.edit.NumEdit</i> <i>method</i> ), 276	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 991	
<i>get_curve()</i> ( <i>pylablib.devices.Lakeshore.base.Lakeshore218</i> <i>method</i> ), 673	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1006	
<i>get_curve_header()</i> ( <i>py-</i> <i>lablib.devices.Lakeshore.base.Lakeshore218</i> <i>method</i> ), 673	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1002	
<i>get_cycle_timings()</i> ( <i>py-</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 528	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1011	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 515	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 710	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 510	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 759	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 530	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 776	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 540	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 784	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 581	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa</i> <i>method</i> ), 807	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 592	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam</i> <i>method</i> ), 790	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 587	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame</i> <i>method</i> ), 799	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 618	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 830	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 642	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 849	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 638	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb</i> <i>method</i> ), 844	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 658	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 907	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 653	<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1028	
<i>get_data_dimensions()</i> ( <i>py-</i> <i>lablib.devices.interface.camera.IAttributeCamera</i>	<i>get_data_format()</i> ( <i>py-</i> <i>lablib.devices.Tektronix.base.DPO2000</i>	

- method*), 896
- `get_data_format()` (py-lablib.devices.Tektronix.base.ITektronixScope *method*), 884
- `get_data_format()` (py-lablib.devices.Tektronix.base.TDS2000 *method*), 889
- `get_data_pts_range()` (py-lablib.devices.Tektronix.base.DPO2000 *method*), 896
- `get_data_pts_range()` (py-lablib.devices.Tektronix.base.ITektronixScope *method*), 884
- `get_data_pts_range()` (py-lablib.devices.Tektronix.base.TDS2000 *method*), 889
- `get_default_addr()` (py-lablib.devices.Thorlabs.elliptec.ElliptecMotor *method*), 912
- `get_default_axis()` (py-lablib.devices.SmarAct.MCS2.MCS2 *method*), 870
- `get_default_channel()` (py-lablib.devices.HighFinesse.wlm.WLM *method*), 627
- `get_defaults_list()` (py-lablib.core.utils.functions.FunctionSignature *method*), 420
- `get_defect_correct_mode()` (py-lablib.devices.DCAM.DCAM.DCAMCamera *method*), 617
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.Array1DWrapper *method*), 153
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper *method*), 157
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper *method*), 157
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper *method*), 159
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper *method*), 159
- `get_deleted()` (pylablib.core.dataproc.table\_wrap.Series1DWrapper *method*), 155
- `get_description()` (pylablib.core.devio.hid.HIDDevice *method*), 195
- `get_detector_offset()` (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph *method*), 546
- `get_detector_size()` (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera *method*), 515
- `get_detector_size()` (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera *method*), 508
- `get_detector_size()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 529
- `get_detector_size()` (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera *method*), 540
- `get_detector_size()` (py-lablib.devices.Basler.pylon.BaslerPylonCamera *method*), 578
- `get_detector_size()` (py-lablib.devices.BitFlow.BitFlow.BitFlowCamera *method*), 592
- `get_detector_size()` (py-lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber *method*), 586
- `get_detector_size()` (py-lablib.devices.DCAM.DCAM.DCAMCamera *method*), 617
- `get_detector_size()` (py-lablib.devices.IMAQ.IMAQ.IMAQCamera *method*), 642
- `get_detector_size()` (py-lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber *method*), 634
- `get_detector_size()` (py-lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera *method*), 658
- `get_detector_size()` (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera *method*), 652
- `get_detector_size()` (py-lablib.devices.interface.camera.IAttributeCamera *method*), 997
- `get_detector_size()` (py-lablib.devices.interface.camera.IBinROICamera *method*), 986
- `get_detector_size()` (py-lablib.devices.interface.camera.ICamera *method*), 991
- `get_detector_size()` (py-lablib.devices.interface.camera.IExposureCamera *method*), 1006
- `get_detector_size()` (py-lablib.devices.interface.camera.IGrabberAttributeCamera *method*), 1002
- `get_detector_size()` (py-lablib.devices.interface.camera.IROICamera *method*), 1011
- `get_detector_size()` (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera *method*), 709
- `get_detector_size()` (py-lablib.devices.PCO.SC2.PCOSC2Camera *method*), 758

get_detector_size()	(py-	lablib.devices.Andor.AndorSDK3.AndorSDK3Camera
lablib.devices.Photometrics.pvcam.PvcamCamera	method), 538	
method), 774	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Andor.Shamrock.ShamrockSpectrograph
lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera	method), 545	
method), 783	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Arcus.performax.GenericPerformaxStage
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera	method), 551	
method), 807	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Arcus.performax.Performax2EXStage
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera	method), 557	
method), 790	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Arcus.performax.Performax4EXStage
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera	method), 555	
method), 799	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Arcus.performax.PerformaxDMXJSAStage
lablib.devices.PrincetonInstruments.picam.PicamCamera	method), 562	
method), 829	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Attocube.anc300.ANC300
lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera	method), 566	
method), 849	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.Basler.pylon.BaslerPylonCamera
lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber	method), 578	
method), 842	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.BitFlow.BitFlow.BitFlowCamera
lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera	method), 592	
method), 907	get_device_info()	(py-
get_detector_size()	(py-	lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber
lablib.devices.uc480.uc480.UC480Camera	method), 586	
method), 1027	get_device_info()	(py-
get_device()	(pylablib.core.utils.rpyc_utils.DeviceService	lablib.devices.DCAM.DCAM.DCAMCamera
method), 447	method), 615	
get_device_class()	(py-	get_device_info()
lablib.core.utils.rpyc_utils.DeviceService	method), 623	(py-
method), 447	get_device_info()	(py-
get_device_info()	(in module	py-
lablib.devices.Basler.pylon), 575	lablib.devices.HighFinesse.wlm.WLM method),	
get_device_info()	(in module	py-
lablib.devices.NI.daq), 718	626	
get_device_info()	(in module	py-
lablib.devices.SmarAct.scu3d), 874	get_device_info()	(py-
get_device_info()	(py-	lablib.devices.Hubner.Cobolt.Cobolt method),
lablib.devices.Agilent.pressure.XGS600	method), 630	
method), 506	get_device_info()	(py-
get_device_info()	(py-	lablib.devices.IMAQ.IMAQ.IMAQCamera
lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera	method), 642	
method), 515	get_device_info()	(py-
get_device_info()	(py-	lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber
lablib.devices.AlliedVision.Bonito.IBonitoCamera	method), 634	
method), 508	get_device_info()	(py-
get_device_info()	(py-	lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera
lablib.devices.Andor.AndorSDK2.AndorSDK2Camera	method), 658	
method), 524	get_device_info()	(py-
get_device_info()	(py-	lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera
	method), 651	
	(py-	get_device_info()
		(py-



`lablib.devices.KJL.base.KJL300` (method), 663  
`get_device_info()` (`py-lablib.devices.LaserQuantum.base.Finesse` method), 683  
`get_device_info()` (`py-lablib.devices.Leybold.base.GenericITR` method), 686  
`get_device_info()` (`py-lablib.devices.Leybold.base.ITR90` method), 688  
`get_device_info()` (`py-lablib.devices.LighthousePhotonics.base.SproutG` method), 690  
`get_device_info()` (`py-lablib.devices.Lumel.base.LumelRE72Controller` method), 692  
`get_device_info()` (`py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera` method), 708  
`get_device_info()` (`py-lablib.devices.Newport.picomotor.Picomotor8742` method), 736  
`get_device_info()` (`pylablib.devices.NI.daq.NIDAQ` method), 719  
`get_device_info()` (`py-lablib.devices.Omron.base.OmronE5xCController` method), 746  
`get_device_info()` (`py-lablib.devices.Ophir.base.VegaPowerMeter` method), 751  
`get_device_info()` (`py-lablib.devices.PCO.SC2.PCOSC2Camera` method), 756  
`get_device_info()` (`py-lablib.devices.Photometrics.pvcam.PvcamCamera` method), 773  
`get_device_info()` (`py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` method), 783  
`get_device_info()` (`py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFluxCamera` method), 807  
`get_device_info()` (`py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera` method), 790  
`get_device_info()` (`py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera` method), 799  
`get_device_info()` (`py-lablib.devices.PrincetonInstruments.picam.PicamCamera` method), 828  
`get_device_info()` (`py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera` method), 849  
`get_device_info()` (`py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` method), 842  
`get_device_info()` (`py-lablib.devices.SmarAct.MCS2.MCS2` method), 869  
`get_device_info()` (`py-lablib.devices.SmarAct.scu3d.SC3D` method), 874  
`get_device_info()` (`py-lablib.devices.Thorlabs.elliptec.ElliptecMotor` method), 913  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.BasicKinesisDevice` method), 918  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.KinesisDevice` method), 922  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.KinesisMotor` method), 932  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController` method), 940  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor` method), 936  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.KinesisQuadDetector` method), 944  
`get_device_info()` (`py-lablib.devices.Thorlabs.kinesis.MFF` method), 926  
`get_device_info()` (`py-lablib.devices.Thorlabs.misc.GenericPM` method), 946  
`get_device_info()` (`py-lablib.devices.Thorlabs.misc.PM160` method), 951  
`get_device_info()` (`py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera` method), 904  
`get_device_info()` (`py-lablib.devices.Topica.ibeam.TopicalBeam` method), 969  
`get_device_info()` (`py-lablib.devices.uc480.uc480.UC480Camera` method), 1025  
`get_device_info()` (`py-lablib.devices.Windows.joystick.Joystick` method), 988  
`get_device_info()` (`py-lablib.devices.Pfeiffer.base.DPG202` method),

768		method), 555
<code>get_device_number()</code>	(py- lablib.devices.Arcus.performax.GenericPerformaxStage method), 551	<code>get_device_variable()</code> (py- lablib.devices.Arcus.performax.PerformaxDMXJSASStage method), 562
<code>get_device_number()</code>	(py- lablib.devices.Arcus.performax.Performax2EXStage method), 557	<code>get_device_variable()</code> (py- lablib.devices.Arduino.base.IArduinoDevice method), 565
<code>get_device_number()</code>	(py- lablib.devices.Arcus.performax.Performax4EXStage method), 555	<code>get_device_variable()</code> (py- lablib.devices.Attocube.anc300.ANC300 method), 569
<code>get_device_number()</code>	(py- lablib.devices.Arcus.performax.PerformaxDMXJSASStage method), 562	<code>get_device_variable()</code> (py- lablib.devices.Attocube.anc350.ANC350 method), 573
<code>get_device_status()</code>	(py- lablib.devices.SmarAct.MCS2.MCS2 method), 870	<code>get_device_variable()</code> (py- lablib.devices.AWG.generic.GenericAWG method), 459
<code>get_device_status_n()</code>	(py- lablib.devices.SmarAct.MCS2.MCS2 method), 870	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.Agilent33220A method), 469
<code>get_device_variable()</code>	(py- lablib.core.devio.comm_backend.ICommBackendWrapper method), 192	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.Agilent33500 method), 463
<code>get_device_variable()</code>	(py- lablib.core.devio.interface.IDevice method), 197	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.InstekAFG2000 method), 481
<code>get_device_variable()</code>	(py- lablib.core.devio.SCPI.SCPIDevice method), 168	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.InstekAFG2225 method), 475
<code>get_device_variable()</code>	(py- lablib.devices.Agilent.pressure.XGS600 method), 506	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.RigolDG1000 method), 500
<code>get_device_variable()</code>	(py- lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 515	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.RSInstekAFG21000 method), 487
<code>get_device_variable()</code>	(py- lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 510	<code>get_device_variable()</code> (py- lablib.devices.AWG.specific.TektronixAFG1000 method), 494
<code>get_device_variable()</code>	(py- lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 530	<code>get_device_variable()</code> (py- lablib.devices.Basler.pylon.BaslerPylonCamera method), 581
<code>get_device_variable()</code>	(py- lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 541	<code>get_device_variable()</code> (py- lablib.devices.BitFlow.BitFlow.BitFlowCamera method), 592
<code>get_device_variable()</code>	(py- lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 549	<code>get_device_variable()</code> (py- lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 588
<code>get_device_variable()</code>	(py- lablib.devices.Arcus.performax.GenericPerformaxStage method), 552	<code>get_device_variable()</code> (py- lablib.devices.Conrad.base.RelayBoard method), 598
<code>get_device_variable()</code>	(py- lablib.devices.Arcus.performax.Performax2EXStage method), 557	<code>get_device_variable()</code> (py- lablib.devices.Cryocon.base.Cryocon1x method), 601
<code>get_device_variable()</code>	(py- lablib.devices.Arcus.performax.Performax4EXStage method), 555	<code>get_device_variable()</code> (py- lablib.devices.Cryomagnetics.base.LM500 method), 555

<i>method</i> ), 606		<i>method</i> ), 668	
<code>get_device_variable()</code> (py-lablib.devices.Cryomagnetics.base.LM510 <i>method</i> ), 609		<code>get_device_variable()</code> (py-lablib.devices.KJL.base.KJL300 <i>method</i> ), 664	
<code>get_device_variable()</code> (py-lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 618		<code>get_device_variable()</code> (py-lablib.devices.Lakeshore.base.Lakeshore218 <i>method</i> ), 674	
<code>get_device_variable()</code> (py-lablib.devices.ElektroAutomatik.base.PS2000B <i>method</i> ), 624		<code>get_device_variable()</code> (py-lablib.devices.Lakeshore.base.Lakeshore370 <i>method</i> ), 679	
<code>get_device_variable()</code> (py-lablib.devices.HighFinesse.wlm.WLM <i>method</i> ), 629		<code>get_device_variable()</code> (py-lablib.devices.LaserQuantum.base.Finesse <i>method</i> ), 684	
<code>get_device_variable()</code> (py-lablib.devices.Hubner.Cobolt.Cobolt <i>method</i> ), 632		<code>get_device_variable()</code> (py-lablib.devices.Leybold.base.GenericITR <i>method</i> ), 686	
<code>get_device_variable()</code> (py-lablib.devices.IMAQ.IMAQ.IMAQCamera <i>method</i> ), 642		<code>get_device_variable()</code> (py-lablib.devices.Leybold.base.ITR90 <i>method</i> ), 688	
<code>get_device_variable()</code> (py-lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber <i>method</i> ), 638		<code>get_device_variable()</code> (py-lablib.devices.LighthousePhotonics.base.SproutG <i>method</i> ), 691	
<code>get_device_variable()</code> (py-lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera <i>method</i> ), 658		<code>get_device_variable()</code> (py-lablib.devices.Lumel.base.LumelRE72Controller <i>method</i> ), 693	
<code>get_device_variable()</code> (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera <i>method</i> ), 653		<code>get_device_variable()</code> (py-lablib.devices.M2.base.ICEBlocDevice <i>method</i> ), 697	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.IAttributeCamera <i>method</i> ), 997		<code>get_device_variable()</code> (py-lablib.devices.M2.emm.EMM <i>method</i> ), 700	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.IBinROICamera <i>method</i> ), 1016		<code>get_device_variable()</code> (py-lablib.devices.M2.solstis.Solstis <i>method</i> ), 706	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.ICamera <i>method</i> ), 993		<code>get_device_variable()</code> (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 710	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.IExposureCamera <i>method</i> ), 1006		<code>get_device_variable()</code> (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice <i>method</i> ), 716	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.IGrabberAttributeCamera <i>method</i> ), 1002		<code>get_device_variable()</code> (py-lablib.devices.Newport.picomotor.Picomotor8742 <i>method</i> ), 738	
<code>get_device_variable()</code> (py-lablib.devices.interface.camera.IROICamera <i>method</i> ), 1011		<code>get_device_variable()</code> (py-lablib.devices.NI.daq.NIDAQ <i>method</i> ), 724	
<code>get_device_variable()</code> (py-lablib.devices.interface.stage.IMultiaxisStage <i>method</i> ), 1022		<code>get_device_variable()</code> (py-lablib.devices.NKT.interbus.GenericInterbusDevice <i>method</i> ), 726	
<code>get_device_variable()</code> (py-lablib.devices.interface.stage.IStage <i>method</i> ), 1021		<code>get_device_variable()</code> (py-lablib.devices.NKT.interbus.GenericInterbusModule <i>method</i> ), 728	
<code>get_device_variable()</code> (py-lablib.devices.Keithley.multimeter.Keithley2110 <i>method</i> ), 606		<code>get_device_variable()</code> (py-lablib.devices.NKT.interbus.IInterbusModule <i>method</i> ), 727	
		<code>get_device_variable()</code> (py-	

<code>lablib.devices.NKT.interbus.InterbusSystem</code> <code>method</code> ), 734	<code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</code> <code>method</code> ), 790
<code>get_device_variable()</code> (py- <code>lablib.devices.NKT.interbus.SuperKExtremeInterbusModule</code> <code>method</code> ), 729	<code>get_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> <code>method</code> ), 799
<code>get_device_variable()</code> (py- <code>lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule</code> <code>method</code> ), 730	<code>get_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.GenericPIController</code> <code>method</code> ), 815
<code>get_device_variable()</code> (py- <code>lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule</code> <code>method</code> ), 731	<code>get_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.PIE515</code> <code>method</code> ), 821
<code>get_device_variable()</code> (py- <code>lablib.devices.NKT.interbus.SuperKSelectInterbusModule</code> <code>method</code> ), 732	<code>get_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.PIE516</code> <code>method</code> ), 818
<code>get_device_variable()</code> (py- <code>lablib.devices.Omron.base.OmronE5xCController</code> <code>method</code> ), 747	<code>get_device_variable()</code> (py- <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> <code>method</code> ), 830
<code>get_device_variable()</code> (py- <code>lablib.devices.Ophir.base.OphirDevice</code> <code>method</code> ), 750	<code>get_device_variable()</code> (py- <code>lablib.devices.Rigol.power_supply.DP1116A</code> <code>method</code> ), 836
<code>get_device_variable()</code> (py- <code>lablib.devices.Ophir.base.VegaPowerMeter</code> <code>method</code> ), 753	<code>get_device_variable()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> <code>method</code> ), 849
<code>get_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.DD100</code> <code>method</code> ), 743	<code>get_device_variable()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> <code>method</code> ), 844
<code>get_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.EPC04</code> <code>method</code> ), 745	<code>get_device_variable()</code> (py- <code>lablib.devices.Sirah.Matisse.SirahMatisse</code> <code>method</code> ), 861
<code>get_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.OZOpticsDevice</code> <code>method</code> ), 740	<code>get_device_variable()</code> (py- <code>lablib.devices.SmarAct.MCS2.MCS2</code> <code>method</code> ), 872
<code>get_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.TF100</code> <code>method</code> ), 742	<code>get_device_variable()</code> (py- <code>lablib.devices.SmarAct.scu3d.SCU3D</code> <code>method</code> ), 875
<code>get_device_variable()</code> (py- <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> <code>method</code> ), 759	<code>get_device_variable()</code> (py- <code>lablib.devices.Standa.base.Standa8SMC</code> <code>method</code> ), 879
<code>get_device_variable()</code> (py- <code>lablib.devices.Pfeiffer.base.DPG202</code> <code>method</code> ), 768	<code>get_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.DPO2000</code> <code>method</code> ), 896
<code>get_device_variable()</code> (py- <code>lablib.devices.Pfeiffer.base.TPG260</code> <code>method</code> ), 766	<code>get_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.ITektronixScope</code> <code>method</code> ), 885
<code>get_device_variable()</code> (py- <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 776	<code>get_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.TDS2000</code> <code>method</code> ), 889
<code>get_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 784	<code>get_device_variable()</code> (py- <code>lablib.devices.Thorlabs.elliptec.ElliptecMotor</code> <code>method</code> ), 915
<code>get_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlipper</code> <code>method</code> ), 807	<code>get_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.BasicKinesisDevice</code> <code>method</code> ), 918
<code>get_device_variable()</code> (py- <code>get_device_variable()</code>	<code>get_device_variable()</code> (py- <code>get_device_variable()</code>

<i>lablib.devices.Thorlabs.kinesis.KinesisDevice</i> method), 922	<i>lablib.devices.Voltcraft.multimeter.VC880</i> method), 986
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> method), 932	<i>get_device_variable()</i> (py- <i>lablib.devices.Windows.joystick.Joystick</i> method), 988
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoController</i> method), 940	<i>get_devices_number()</i> (in module <i>py- lablib.devices.SmarAct.MCS2</i> ), 868
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</i> method), 937	<i>get_devices_number()</i> (in module <i>py- lablib.devices.SmarAct.scu3d</i> ), 874
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</i> method), 944	<i>get_dictionary_line()</i> (py- <i>lablib.core.fileio.savefile.DictionaryOutputFileFormat</i> method), 227
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.kinesis.MFF</i> method), 926	<i>get_digital_gain()</i> (py- <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 515
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.misc.GenericPM</i> method), 947	<i>get_digital_gain()</i> (py- <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> method), 509
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.misc.PM160</i> method), 951	<i>get_digital_input()</i> (py- <i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 558
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.serial.FW</i> method), 958	<i>get_digital_input()</i> (py- <i>lablib.devices.Arcus.performax.Performax4EXStage</i> method), 555
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.serial.FWv1</i> method), 962	<i>get_digital_input()</i> (py- <i>lablib.devices.Arcus.performax.PerformaxDMXJSAStage</i> method), 562
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.serial.MDT69xA</i> method), 965	<i>get_digital_input_parameters()</i> (py- <i>lablib.devices.NI.daq.NIDAQ</i> method), 720
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.serial.ThorlabsSerialInterface</i> method), 955	<i>get_digital_input_register()</i> (py- <i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 558
<i>get_device_variable()</i> (py- <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> method), 907	<i>get_digital_input_register()</i> (py- <i>lablib.devices.Arcus.performax.Performax4EXStage</i> method), 555
<i>get_device_variable()</i> (py- <i>lablib.devices.Toptica.ibeam.TopicalIBeam</i> method), 970	<i>get_digital_input_register()</i> (py- <i>lablib.devices.Arcus.performax.PerformaxDMXJSAStage</i> method), 562
<i>get_device_variable()</i> (py- <i>lablib.devices.Trinamic.base.TMCM1110</i> method), 975	<i>get_digital_output()</i> (py- <i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 558
<i>get_device_variable()</i> (py- <i>lablib.devices.Trinamic.base.TMCMx110</i> method), 977	<i>get_digital_output()</i> (py- <i>lablib.devices.Arcus.performax.Performax4EXStage</i> method), 555
<i>get_device_variable()</i> (py- <i>lablib.devices.uc480.uc480.UC480Camera</i> method), 1028	<i>get_digital_output()</i> (py- <i>lablib.devices.Arcus.performax.PerformaxDMXJSAStage</i> method), 562
<i>get_device_variable()</i> (py- <i>lablib.devices.Voltcraft.multimeter.VC7055</i> method), 982	<i>get_digital_output_channels()</i> (py- <i>lablib.devices.NI.daq.NIDAQ</i> method), 721
<i>get_device_variable()</i> (py-	<i>get_digital_output_parameters()</i> (py- <i>lablib.devices.NI.daq.NIDAQ</i> method), 721
	<i>get_digital_output_register()</i> (py- <i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 558



get_digital_output_register()	(py-lablib.devices.Arcus.performax.Performax4EXStage method), 500
get_digital_output_register()	(py-lablib.devices.AWG.generic.GenericAWG method), 555
get_digital_output_register()	(py-lablib.devices.AWG.generic.GenericAWG method), 562
get_digital_outputs()	(py-lablib.devices.NI.daq.NIDAQ method), 721
get_diode_power()	(py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
get_diode_power_lowlevel()	(py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
get_diode_power_waveform()	(py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857
get_display_channel()	(py-lablib.devices.Pfeiffer.base.TPG260 method), 765
get_display_resolution()	(py-lablib.devices.Pfeiffer.base.TPG260 method), 765
get_display_units()	(py-lablib.devices.Cryocon.base.CryoconIx method), 600
get_double_image_mode()	(py-lablib.devices.PCO.SC2.PCOSC2Camera method), 759
get_drive_current()	(py-lablib.devices.Toptica.ibeam.TopticaIBeam method), 969
get_drive_parameters()	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935
get_dtype()	(pylablib.core.fileio.savefile.TableBinaryOutputFileFormat method), 227
get_duty_cycle()	(py-lablib.devices.AWG.generic.GenericAWG method), 457
get_duty_cycle()	(py-lablib.devices.AWG.specific.Agilent33220A method), 469
get_duty_cycle()	(py-lablib.devices.AWG.specific.Agilent33500 method), 463
get_duty_cycle()	(py-lablib.devices.AWG.specific.InstekAFG2000 method), 481
get_duty_cycle()	(py-lablib.devices.AWG.specific.InstekAFG2225 method), 475
get_duty_cycle()	(py-lablib.devices.AWG.specific.RigolDG1000 method), 487
get_duty_cycle()	(py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 487
get_duty_cycle()	(py-lablib.devices.AWG.specific.TektronixAFG1000 method), 494
get_edge_trigger_coupling()	(py-lablib.devices.Tektronix.base.DPO2000 method), 896
get_edge_trigger_coupling()	(py-lablib.devices.Tektronix.base.ITektronixScope method), 882
get_edge_trigger_coupling()	(py-lablib.devices.Tektronix.base.TDS2000 method), 889
get_edge_trigger_slope()	(py-lablib.devices.Tektronix.base.DPO2000 method), 896
get_edge_trigger_slope()	(py-lablib.devices.Tektronix.base.ITektronixScope method), 882
get_edge_trigger_slope()	(py-lablib.devices.Tektronix.base.TDS2000 method), 889
get_edge_trigger_source()	(py-lablib.devices.Tektronix.base.DPO2000 method), 896
get_edge_trigger_source()	(py-lablib.devices.Tektronix.base.ITektronixScope method), 882
get_edge_trigger_source()	(py-lablib.devices.Tektronix.base.TDS2000 method), 889
get_element_position()	(py-lablib.core.gui.widgets.container.IQWidgetContainer method), 243
get_element_position()	(py-lablib.core.gui.widgets.container.QDialogContainer method), 257
get_element_position()	(py-lablib.core.gui.widgets.container.QFrameContainer method), 252
get_element_position()	(py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 262
get_element_position()	(py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 266
get_element_position()	(py-lablib.core.gui.widgets.container.QWidgetContainer method), 248
get_element_position()	(py-lablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget method), 248

method), 280

get\_element\_position() (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 282

get\_element\_position() (pylablib.core.gui.widgets.param\_table.ParamTable method), 293

get\_element\_position() (pylablib.core.gui.widgets.param\_table.StatusTable method), 303

get\_EMCCD\_gain() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526

get\_enabled\_channels() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 934

get\_encoder() (pylablib.devices.Arcus.performax.Performax2EXStage method), 558

get\_encoder() (pylablib.devices.Arcus.performax.Performax4EXStage method), 553

get\_encoder() (pylablib.devices.Standa.base.Standa8SMC method), 878

get\_energy() (pylablib.devices.Ophir.base.VegaPowerMeter method), 751

get\_engine\_type() (pylablib.devices.Standa.base.Standa8SMC method), 878

get\_entry() (pylablib.core.utils.dictionary.Dictionary method), 378

get\_entry() (pylablib.core.utils.dictionary.DictionaryPoint method), 389

get\_entry() (pylablib.core.utils.dictionary.FilterTree method), 406

get\_entry() (pylablib.core.utils.dictionary.PrefixTree method), 398

get\_environ\_folder() (in module pylablib.devices.utils.load\_lib), 1032

get\_error\_code() (pylablib.devices.Pfeiffer.base.DPG202 method), 768

get\_error\_state() (pylablib.devices.Hubner.Cobolt.Cobolt method), 630

get\_esr() (pylablib.core.devio.SCPi.SCPIDevice method), 166

get\_esr() (pylablib.devices.AWG.generic.GenericAWG method), 459

get\_esr() (pylablib.devices.AWG.specific.Agilent33220A method), 469

get\_esr() (pylablib.devices.AWG.specific.Agilent33500 method), 463

get\_esr() (pylablib.devices.AWG.specific.InstekAFG2000 method), 481

get\_esr() (pylablib.devices.AWG.specific.InstekAFG2225 method), 475

get\_esr() (pylablib.devices.AWG.specific.RigolDG1000 method), 500

get\_esr() (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 487

get\_esr() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 494

get\_esr() (pylablib.devices.Cryocon.base.Cryocon1x method), 601

get\_esr() (pylablib.devices.Cryomagnetics.base.LM500 method), 606

get\_esr() (pylablib.devices.Cryomagnetics.base.LM510 method), 609

get\_esr() (pylablib.devices.Keithley.mmultimeter.Keithley2110 method), 668

get\_esr() (pylablib.devices.Lakeshore.base.Lakeshore218 method), 674

get\_esr() (pylablib.devices.Lakeshore.base.Lakeshore370 method), 679

get\_esr() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 821

get\_esr() (pylablib.devices.Rigol.power\_supply.DP1116A method), 836

get\_esr() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 861

get\_esr() (pylablib.devices.Tektronix.base.DPO2000 method), 896

get\_esr() (pylablib.devices.Tektronix.base.ITektronixScope method), 885

get\_esr() (pylablib.devices.Tektronix.base.TDS2000 method), 889

get\_esr() (pylablib.devices.Thorlabs.misc.GenericPM method), 947

get\_esr() (pylablib.devices.Thorlabs.misc.PM160 method), 951

get\_esr() (pylablib.devices.Thorlabs.serial.FW method), 959

get\_esr() (pylablib.devices.Thorlabs.serial.FWv1 method), 962

get\_esr() (pylablib.devices.Thorlabs.serial.MDT69xA method), 965

get\_esr() (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955

get\_esr() (pylablib.devices.Voltcraft.mmultimeter.VC7055 method), 982

get\_etalon\_lock\_status() (pylablib.devices.M2.solstis.Solstis method), 703

get\_ethernet\_parameters() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 737

get\_events() (pylablib.devices.Windows.joystick.Joystick method), 988

get\_exec\_counter() (pylablib.devices.Windows.joystick.Joystick method), 988

<code>lablib.core.thread.controller.QTaskThread</code> <code>method</code> ), 358	<code>get_ext()</code> ( <code>pylablib.core.fileio.location.LocationName</code> <code>method</code> ), 217
<code>get_exec_counter()</code> ( <code>py-</code> <code>lablib.core.thread.controller.QThreadController</code> <code>method</code> ), 349	<code>get_ext_trigger_parameters()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 527
<code>get_executable()</code> ( <code>in module py-</code> <code>lablib.core.utils.module</code> ), 438	<code>get_ext_trigger_parameters()</code> ( <code>py-</code> <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 616
<code>get_export_clock_terminal()</code> ( <code>py-</code> <code>lablib.devices.NI.daq.NIDAQ</code> <code>method</code> ), 719	<code>get_ext_trigger_parameters()</code> ( <code>py-</code> <code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> <code>method</code> ), 905
<code>get_exposure()</code> ( <code>pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</code> <code>method</code> ), 515	<code>get_external_input_modes()</code> ( <code>py-</code> <code>lablib.devices.Attocube.anc300.ANC300</code> <code>method</code> ), 568
<code>get_exposure()</code> ( <code>pylablib.devices.AlliedVision.Bonito.IBonitoCamera</code> <code>method</code> ), 508	<code>get_fan_mode()</code> ( <code>pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 526
<code>get_exposure()</code> ( <code>pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 528	<code>get_fan_mode()</code> ( <code>pylablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 773
<code>get_exposure()</code> ( <code>pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> <code>method</code> ), 538	<code>get_fast_kinetic_mode_parameters()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 528
<code>get_exposure()</code> ( <code>pylablib.devices.Basler.pylon.BaslerPylonCamera</code> <code>method</code> ), 579	<code>get_fast_scan_status()</code> ( <code>py-</code> <code>lablib.devices.M2.solstis.Solstis</code> <code>method</code> ), 765
<code>get_exposure()</code> ( <code>pylablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 616	<code>get_fastpiezo_ctl_params()</code> ( <code>py-</code> <code>lablib.devices.Sirah.Matisse.SirahMatisse</code> <code>method</code> ), 860
<code>get_exposure()</code> ( <code>pylablib.devices.HighFinesse.wlm.WLM</code> <code>method</code> ), 627	<code>get_fastpiezo_ctl_status()</code> ( <code>py-</code> <code>lablib.devices.Sirah.Matisse.SirahMatisse</code> <code>method</code> ), 859
<code>get_exposure()</code> ( <code>pylablib.devices.interface.camera.IExposureCamera</code> <code>method</code> ), 1005	<code>get_fastpiezo_position()</code> ( <code>py-</code> <code>lablib.devices.Sirah.Matisse.SirahMatisse</code> <code>method</code> ), 860
<code>get_exposure()</code> ( <code>pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</code> <code>method</code> ), 709	<code>get_file_for_arbitrary_time()</code> ( <code>in module py-</code> <code>lablib.core.utils.files</code> ), 412
<code>get_exposure()</code> ( <code>pylablib.devices.PCO.SC2.PCOSC2Camera</code> <code>method</code> ), 757	<code>get_file_for_file_operations()</code> ( <code>in module py-</code> <code>lablib.core.utils.files</code> ), 412
<code>get_exposure()</code> ( <code>pylablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 773	<code>get_filesystem_path()</code> ( <code>py-</code> <code>lablib.core.fileio.location.FolderFileSystemDataLocation</code> <code>method</code> ), 221
<code>get_exposure()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 783	<code>get_filesystem_path()</code> ( <code>py-</code> <code>lablib.core.fileio.location.IFileSystemDataLocation</code> <code>method</code> ), 219
<code>get_exposure()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera</code> <code>method</code> ), 807	<code>get_filesystem_path()</code> ( <code>py-</code> <code>lablib.core.fileio.location.PrefixedFileSystemDataLocation</code> <code>method</code> ), 221
<code>get_exposure()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera</code> <code>method</code> ), 790	<code>get_filesystem_path()</code> ( <code>py-</code> <code>lablib.core.fileio.location.SingleFileSystemDataLocation</code> <code>method</code> ), 220
<code>get_exposure()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera</code> <code>method</code> ), 799	<code>get_fill_status()</code> ( <code>py-</code> <code>lablib.devices.Cryomagnetics.base.LM500</code> <code>method</code> ), 605
<code>get_exposure()</code> ( <code>pylablib.devices.PrincetonInstruments.picam.PicamCamera</code> <code>method</code> ), 829	<code>get_fill_status()</code> ( <code>py-</code> <code>lablib.devices.Cryomagnetics.base.LM510</code> <code>method</code> ), 605
<code>get_exposure()</code> ( <code>pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> <code>method</code> ), 908	
<code>get_exposure()</code> ( <code>pylablib.devices.uc480.uc480.UC480Camera</code> <code>method</code> ), 1028	
<code>get_exposure_control_mode()</code> ( <code>py-</code> <code>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</code> <code>method</code> ), 515	
<code>get_exposure_control_mode()</code> ( <code>py-</code> <code>lablib.devices.AlliedVision.Bonito.IBonitoCamera</code> <code>method</code> ), 508	
<code>get_exposure_mode()</code> ( <code>py-</code> <code>lablib.devices.HighFinesse.wlm.WLM</code> <code>method</code> ), 627	



- method*), 609
- `get_filter()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` *method*), 547
- `get_filter_info()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` *method*), 547
- `get_filter_settings()` (`pylablib.devices.Lakeshore.base.Lakeshore218` *method*), 674
- `get_filter_settings()` (`pylablib.devices.Lakeshore.base.Lakeshore370` *method*), 679
- `get_fine_tuning_status()` (`pylablib.devices.M2.emm.EMM` *method*), 698
- `get_fine_tuning_status()` (`pylablib.devices.M2.solstis.Solstis` *method*), 702
- `get_fine_wavelength()` (`pylablib.devices.M2.emm.EMM` *method*), 698
- `get_fine_wavelength()` (`pylablib.devices.M2.solstis.Solstis` *method*), 702
- `get_first_empty_column()` (in module `pylablib.core.gui.utils`), 310
- `get_first_empty_row()` (in module `pylablib.core.gui.utils`), 310
- `get_flipper_parameters()` (`pylablib.devices.Thorlabs.kinesis.MFF` *method*), 925
- `get_flipper_port()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` *method*), 547
- `get_focus_mirror_position()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` *method*), 548
- `get_focus_mirror_position_max()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` *method*), 548
- `get_frame()` (`pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera` *method*), 905
- `get_frame_delay()` (`pylablib.devices.PCO.SC2.PCOSC2Camera` *method*), 757
- `get_frame_format()` (`pylablib.devices.AlliedVision.Bonito.BonitoIMACamera` *method*), 515
- `get_frame_format()` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` *method*), 510
- `get_frame_format()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` *method*), 530
- `get_frame_format()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera` *method*), 541
- `get_frame_format()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera` *method*), 581
- `get_frame_format()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera` *method*), 592
- `get_frame_format()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber` *method*), 588
- `get_frame_format()` (`pylablib.devices.DCAM.DCAM.DCAMCamera` *method*), 618
- `get_frame_format()` (`pylablib.devices.IMAQ.IMAQ.IMAQCamera` *method*), 642
- `get_frame_format()` (`pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` *method*), 638
- `get_frame_format()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera` *method*), 658
- `get_frame_format()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera` *method*), 653
- `get_frame_format()` (`pylablib.devices.interface.camera.IAttributeCamera` *method*), 997
- `get_frame_format()` (`pylablib.devices.interface.camera.IBinROICamera` *method*), 1016
- `get_frame_format()` (`pylablib.devices.interface.camera.ICamera` *method*), 991
- `get_frame_format()` (`pylablib.devices.interface.camera.IExposureCamera` *method*), 1006
- `get_frame_format()` (`pylablib.devices.interface.camera.IGrabberAttributeCamera` *method*), 1002
- `get_frame_format()` (`pylablib.devices.interface.camera.IROICamera` *method*), 1011
- `get_frame_format()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera` *method*), 710
- `get_frame_format()` (`pylablib.devices.PCO.SC2.PCOSC2Camera` *method*), 760
- `get_frame_format()` (`pylablib.devices.Photometrics.pvcam.PvcamCamera` *method*), 776
- `get_frame_format()` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` *method*), 776

<i>method</i> ), 784	<i>method</i> ), 638
get_frame_format() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera <i>method</i> ), 807	(py- get_frame_info_fields() (py- lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera <i>method</i> ), 658
get_frame_format() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera <i>method</i> ), 790	(py- get_frame_info_fields() (py- lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera <i>method</i> ), 653
get_frame_format() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 799	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.IAttributeCamera <i>method</i> ), 997
get_frame_format() lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 830	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.IBinROICamera <i>method</i> ), 1016
get_frame_format() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 849	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.ICamera <i>method</i> ), 992
get_frame_format() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber <i>method</i> ), 844	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.IExposureCamera <i>method</i> ), 1006
get_frame_format() lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 908	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.IGrabberAttributeCamera <i>method</i> ), 1002
get_frame_format() lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1028	(py- get_frame_info_fields() (py- lablib.devices.interface.camera.IROICamera <i>method</i> ), 1011
get_frame_info_fields() lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 515	(py- get_frame_info_fields() (py- lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 711
get_frame_info_fields() lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 510	(py- get_frame_info_fields() (py- lablib.devices.PCO.SC2.PCOSC2Camera <i>method</i> ), 760
get_frame_info_fields() lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 530	(py- get_frame_info_fields() (py- lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 776
get_frame_info_fields() lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 541	(py- get_frame_info_fields() (py- lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 784
get_frame_info_fields() lablib.devices.Basler.pylon.BaslerPylonCamera <i>method</i> ), 581	(py- get_frame_info_fields() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa <i>method</i> ), 807
get_frame_info_fields() lablib.devices.BitFlow.BitFlow.BitFlowCamera <i>method</i> ), 592	(py- get_frame_info_fields() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam <i>method</i> ), 790
get_frame_info_fields() lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber <i>method</i> ), 588	(py- get_frame_info_fields() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame <i>method</i> ), 799
get_frame_info_fields() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 618	(py- get_frame_info_fields() (py- lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 830
get_frame_info_fields() lablib.devices.IMAQ.IMAQ.IMAQCamera <i>method</i> ), 643	(py- get_frame_info_fields() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 849
get_frame_info_fields() lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber <i>method</i> ), 643	(py- get_frame_info_fields() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb <i>method</i> ), 849

<i>method</i> ), 844	<i>method</i> ), 1006
get_frame_info_fields() lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 908	(py- get_frame_info_format() (py- lablib.devices.interface.camera.IGrabberAttributeCamera <i>method</i> ), 1002
get_frame_info_fields() lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1028	(py- get_frame_info_format() (py- lablib.devices.interface.camera.IROICamera <i>method</i> ), 1011
get_frame_info_format() lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 515	(py- get_frame_info_format() (py- lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 711
get_frame_info_format() lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 510	(py- get_frame_info_format() (py- lablib.devices.PCO.SC2.PCOSC2Camera <i>method</i> ), 760
get_frame_info_format() lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 531	(py- get_frame_info_format() (py- lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 776
get_frame_info_format() lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 541	(py- get_frame_info_format() (py- lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 784
get_frame_info_format() lablib.devices.Basler.pylon.BaslerPylonCamera <i>method</i> ), 581	(py- get_frame_info_format() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa <i>method</i> ), 808
get_frame_info_format() lablib.devices.BitFlow.BitFlow.BitFlowCamera <i>method</i> ), 592	(py- get_frame_info_format() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCame <i>method</i> ), 791
get_frame_info_format() lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber <i>method</i> ), 588	(py- get_frame_info_format() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame <i>method</i> ), 800
get_frame_info_format() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 618	(py- get_frame_info_format() (py- lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 830
get_frame_info_format() lablib.devices.IMAQ.IMAQ.IMAQCamera <i>method</i> ), 643	(py- get_frame_info_format() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 850
get_frame_info_format() lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber <i>method</i> ), 638	(py- get_frame_info_format() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb <i>method</i> ), 844
get_frame_info_format() lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera <i>method</i> ), 658	(py- get_frame_info_format() (py- lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 908
get_frame_info_format() lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera <i>method</i> ), 653	(py- get_frame_info_format() (py- lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1028
get_frame_info_format() lablib.devices.interface.camera.IAttributeCamera <i>method</i> ), 997	(py- get_frame_info_period() (py- lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 515
get_frame_info_format() lablib.devices.interface.camera.IBinROICamera <i>method</i> ), 1016	(py- get_frame_info_period() (py- lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 510
get_frame_info_format() lablib.devices.interface.camera.ICamera <i>method</i> ), 992	(py- get_frame_info_period() (py- lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 531
get_frame_info_format() lablib.devices.interface.camera.IExposureCamera	(py- get_frame_info_period() (py- lablib.devices.Andor.AndorSDK3.AndorSDK3Camera

<i>method</i> ), 541		<i>method</i> ), 785	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 581		<code>get_frame_info_period()</code> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> <i>method</i> ), 808	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 592		<code>get_frame_info_period()</code> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> <i>method</i> ), 791	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 588		<code>get_frame_info_period()</code> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 800	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 618		<code>get_frame_info_period()</code> (py- <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 830	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 643		<code>get_frame_info_period()</code> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 850	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 638		<code>get_frame_info_period()</code> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method</i> ), 845	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 659		<code>get_frame_info_period()</code> (py- <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 908	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 654		<code>get_frame_info_period()</code> (py- <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1028	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 997		<code>get_frame_period()</code> (py- <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 516	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1016		<code>get_frame_period()</code> (py- <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 509	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 992		<code>get_frame_period()</code> (py- <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 531	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1007		<code>get_frame_period()</code> (py- <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 538	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1002		<code>get_frame_period()</code> (py- <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 579	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1011		<code>get_frame_period()</code> (py- <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 619	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 711		<code>get_frame_period()</code> (py- <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1006	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 760		<code>get_frame_period()</code> (py- <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 711	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 776		<code>get_frame_period()</code> (py- <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 757	
<code>get_frame_info_period()</code> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 785		<code>get_frame_period()</code> (py- <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 757	

<i>method</i> ), 776	<i>method</i> ), 757
get_frame_period() lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 783	(py- get_frame_timings() (py- lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 774
get_frame_period() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera <i>method</i> ), 808	(py- get_frame_timings() (py- lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 783
get_frame_period() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera <i>method</i> ), 791	(py- get_frame_timings() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera <i>method</i> ), 808
get_frame_period() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 800	(py- get_frame_timings() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera <i>method</i> ), 791
get_frame_period() lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 829	(py- get_frame_timings() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 800
get_frame_period() lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 908	(py- get_frame_timings() (py- lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 829
get_frame_period() lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1028	(py- get_frame_timings() (py- lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 905
get_frame_period_range() lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 905	(py- get_frame_timings() (py- lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1025
get_frame_readout_time() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 616	(py- get_frames_data() (py- lablib.devices.interface.camera.ChunkBufferManager <i>method</i> ), 995
get_frame_timings() lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 516	(py- get_frames_data() (py- lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 797
get_frame_timings() lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 509	(py- get_frames_data() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera.Buff <i>method</i> ), 848
get_frame_timings() lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 528	(py- get_frames_data() (py- lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb <i>method</i> ), 843
get_frame_timings() lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 538	(py- get_frames_status() (py- lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 516
get_frame_timings() lablib.devices.Basler.pylon.BaslerPylonCamera <i>method</i> ), 579	(py- get_frames_status() (py- lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 510
get_frame_timings() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 617	(py- get_frames_status() (py- lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 531
get_frame_timings() lablib.devices.interface.camera.IExposureCamera <i>method</i> ), 1006	(py- get_frames_status() (py- lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 541
get_frame_timings() lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 709	(py- get_frames_status() (py- lablib.devices.Basler.pylon.BaslerPylonCamera <i>method</i> ), 581
get_frame_timings() lablib.devices.PCO.SC2.PCOSC2Camera	(py- get_frames_status() (py- lablib.devices.BitFlow.BitFlow.BitFlowCamera



<i>method</i> ), 592		<i>method</i> ), 808	
get_frames_status() lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber <i>method</i> ), 588	(py-	get_frames_status() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera <i>method</i> ), 791	(py-
get_frames_status() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 619	(py-	get_frames_status() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 800	(py-
get_frames_status() lablib.devices.IMAQ.IMAQ.IMAQCamera <i>method</i> ), 643	(py-	get_frames_status() lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 831	(py-
get_frames_status() lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber <i>method</i> ), 638	(py-	get_frames_status() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 850	(py-
get_frames_status() lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera <i>method</i> ), 659	(py-	get_frames_status() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber <i>method</i> ), 845	(py-
get_frames_status() lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera <i>method</i> ), 654	(py-	get_frames_status() lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera <i>method</i> ), 908	(py-
get_frames_status() lablib.devices.interface.camera.FrameCounter <i>method</i> ), 994	(py-	get_frames_status() lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1027	(py-
get_frames_status() lablib.devices.interface.camera.IAttributeCamera <i>method</i> ), 997	(py-	get_framestamp() lablib.devices.AlliedVision.Bonito.BonitoStatusLineChecker <i>method</i> ), 522	(py-
get_frames_status() lablib.devices.interface.camera.IBinROICamera <i>method</i> ), 1016	(py-	get_framestamp() lablib.devices.interface.camera.StatusLineChecker <i>method</i> ), 1019	(py-
get_frames_status() lablib.devices.interface.camera.ICamera <i>method</i> ), 991	(py-	get_framestamp() lablib.devices.PCO.SC2.StatusLineChecker <i>method</i> ), 763	(py-
get_frames_status() lablib.devices.interface.camera.IExposureCamera <i>method</i> ), 1007	(py-	get_framestamp() lablib.devices.PhotonFocus.PhotonFocus.StatusLineChecker <i>method</i> ), 813	(py-
get_frames_status() lablib.devices.interface.camera.IGrabberAttributeCamera <i>method</i> ), 1002	(py-	get_freq_function_parameters() lablib.devices.Keithley.multimeter.Keithley2110 <i>method</i> ), 667	(py-
get_frames_status() lablib.devices.interface.camera.IROICamera <i>method</i> ), 1012	(py-	get_frequencies() lablib.devices.OZOptics.base.EPC04 <i>method</i> ), 745	(py-
get_frames_status() lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 711	(py-	get_frequency() lablib.devices.Attocube.anc300.ANC300 <i>method</i> ), 567	(py-
get_frames_status() lablib.devices.PCO.SC2.PCOSC2Camera <i>method</i> ), 760	(py-	get_frequency() lablib.devices.Attocube.anc350.ANC350 <i>method</i> ), 572	(py-
get_frames_status() lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 776	(py-	get_frequency() lablib.devices.AWG.generic.GenericAWG <i>method</i> ), 457	(py-
get_frames_status() lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 785	(py-	get_frequency() lablib.devices.AWG.specific.Agilent33220A <i>method</i> ), 469	(py-
get_frames_status() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowFrameGrabber <i>method</i> ), 592	(py-	get_frequency() lablib.devices.AWG.specific.Agilent33500 <i>method</i> ), 469	(py-

- method*), 463
- `get_frequency()` (*py-lablib.devices.AWG.specific.InstekAFG2000* *method*), 481
- `get_frequency()` (*py-lablib.devices.AWG.specific.InstekAFG2225* *method*), 475
- `get_frequency()` (*py-lablib.devices.AWG.specific.RigolDG1000* *method*), 500
- `get_frequency()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000* *method*), 487
- `get_frequency()` (*py-lablib.devices.AWG.specific.TektronixAFG1000* *method*), 494
- `get_frequency()` (*py-lablib.devices.HighFinesse.wlm.WLM* *method*), 627
- `get_frequency()` (*py-lablib.devices.Ophir.base.VegaPowerMeter* *method*), 752
- `get_frequency()` (*py-lablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `get_frequency()` (*py-lablib.devices.Thorlabs.elliptec.ElliptecMotor* *method*), 914
- `get_full_camera_data()` (*py-lablib.devices.PCO.SC2.PCOSC2Camera* *method*), 755
- `get_full_coarse_tuning_status()` (*py-lablib.devices.M2.solstis.Solstis* *method*), 702
- `get_full_data()` (*py-lablib.devices.Toptica.ibeam.TopicalIBeam* *method*), 969
- `get_full_fine_tuning_status()` (*py-lablib.devices.M2.solstis.Solstis* *method*), 701
- `get_full_info()` (*py-lablib.core.devio.comm\_backend.ICommBackendWrapper* *method*), 192
- `get_full_info()` (*py-lablib.core.devio.interface.IDevice* *method*), 197
- `get_full_info()` (*py-lablib.core.devio.SCPI.SCPIDevice* *method*), 168
- `get_full_info()` (*py-lablib.devices.Agilent.pressure.XGS600* *method*), 506
- `get_full_info()` (*py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera* *method*), 516
- `get_full_info()` (*py-lablib.devices.AlliedVision.Bonito.IBonitoCamera* *method*), 510
- `get_full_info()` (*py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera* *method*), 531
- `get_full_info()` (*py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera* *method*), 541
- `get_full_info()` (*py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph* *method*), 549
- `get_full_info()` (*py-lablib.devices.Arcus.performax.GenericPerformaxStage* *method*), 552
- `get_full_info()` (*py-lablib.devices.Arcus.performax.Performax2EXStage* *method*), 558
- `get_full_info()` (*py-lablib.devices.Arcus.performax.Performax4EXStage* *method*), 555
- `get_full_info()` (*py-lablib.devices.Arcus.performax.PerformaxDMX.JSAStage* *method*), 562
- `get_full_info()` (*py-lablib.devices.Arduino.base.IArduinoDevice* *method*), 565
- `get_full_info()` (*py-lablib.devices.Attocube.anc300.ANC300* *method*), 569
- `get_full_info()` (*py-lablib.devices.Attocube.anc350.ANC350* *method*), 573
- `get_full_info()` (*py-lablib.devices.AWG.generic.GenericAWG* *method*), 459
- `get_full_info()` (*py-lablib.devices.AWG.specific.Agilent33220A* *method*), 469
- `get_full_info()` (*py-lablib.devices.AWG.specific.Agilent33500* *method*), 463
- `get_full_info()` (*py-lablib.devices.AWG.specific.InstekAFG2000* *method*), 481
- `get_full_info()` (*py-lablib.devices.AWG.specific.InstekAFG2225* *method*), 475
- `get_full_info()` (*py-lablib.devices.AWG.specific.RigolDG1000* *method*), 500
- `get_full_info()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000* *method*), 487

- method*), 488
- `get_full_info()` (*pylablib.devices.AWG.specific.TektronixAFG1000* *method*), 494
- `get_full_info()` (*pylablib.devices.Basler.pylon.BaslerPylonCamera* *method*), 582
- `get_full_info()` (*pylablib.devices.BitFlow.BitFlow.BitFlowCamera* *method*), 592
- `get_full_info()` (*pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber* *method*), 588
- `get_full_info()` (*pylablib.devices.Conrad.base.RelayBoard* *method*), 598
- `get_full_info()` (*pylablib.devices.Cryocon.base.Cryocon1x* *method*), 601
- `get_full_info()` (*pylablib.devices.Cryomagnetics.base.LM500* *method*), 606
- `get_full_info()` (*pylablib.devices.Cryomagnetics.base.LM510* *method*), 609
- `get_full_info()` (*pylablib.devices.DCAM.DCAM.DCAMCamera* *method*), 619
- `get_full_info()` (*pylablib.devices.ElektroAutomatik.base.PS2000B* *method*), 624
- `get_full_info()` (*pylablib.devices.HighFinesse.wlm.WLM* *method*), 629
- `get_full_info()` (*pylablib.devices.Hubner.Cobolt.Cobolt* *method*), 632
- `get_full_info()` (*pylablib.devices.IMAQ.IMAQ.IMAQCamera* *method*), 643
- `get_full_info()` (*pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber* *method*), 638
- `get_full_info()` (*pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera* *method*), 659
- `get_full_info()` (*pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera* *method*), 654
- `get_full_info()` (*pylablib.devices.interface.camera.IAttributeCamera* *method*), 997
- `get_full_info()` (*pylablib.devices.interface.camera.IBinROICamera* *method*), 1016
- `get_full_info()` (*pylablib.devices.interface.camera.ICamera* *method*), 993
- `get_full_info()` (*pylablib.devices.interface.camera.IExposureCamera* *method*), 1007
- `get_full_info()` (*pylablib.devices.interface.camera.IGrabberAttributeCamera* *method*), 1002
- `get_full_info()` (*pylablib.devices.interface.camera.IROICamera* *method*), 1012
- `get_full_info()` (*pylablib.devices.interface.stage.IMultiaxisStage* *method*), 1022
- `get_full_info()` (*pylablib.devices.interface.stage.IStage* *method*), 1021
- `get_full_info()` (*pylablib.devices.Keithley.mmultimeter.Keithley2110* *method*), 668
- `get_full_info()` (*pylablib.devices.KJL.base.KJL300* *method*), 664
- `get_full_info()` (*pylablib.devices.Lakeshore.base.Lakeshore218* *method*), 674
- `get_full_info()` (*pylablib.devices.Lakeshore.base.Lakeshore370* *method*), 679
- `get_full_info()` (*pylablib.devices.LaserQuantum.base.Finesse* *method*), 684
- `get_full_info()` (*pylablib.devices.Leybold.base.GenericITR* *method*), 686
- `get_full_info()` (*pylablib.devices.Leybold.base.ITR90* *method*), 688
- `get_full_info()` (*pylablib.devices.LighthousePhotonics.base.SproutG* *method*), 691
- `get_full_info()` (*pylablib.devices.Lumel.base.LumelIRE72Controller* *method*), 693
- `get_full_info()` (*pylablib.devices.M2.base.ICEBlocDevice* *method*), 697
- `get_full_info()` (*pylablib.devices.M2.emm.EMM* *method*), 700
- `get_full_info()` (*pylablib.devices.M2.solstis.Solstis* *method*), 706
- `get_full_info()` (*pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera* *method*), 1016



method), 711

get\_full\_info() (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 760

method), 716

get\_full\_info() (py-lablib.devices.Pfeiffer.base.DPG202 method), 768

method), 738

get\_full\_info() (py-lablib.devices.Newport.picomotor.Picomotor8742 method), 766

method), 724

get\_full\_info() (py-lablib.devices.NI.daq.NIDAQ method), 776

method), 726

get\_full\_info() (py-lablib.devices.NKT.interbus.GenericInterbusDevice method), 776

method), 728

get\_full\_info() (py-lablib.devices.NKT.interbus.GenericInterbusModule method), 785

method), 728

get\_full\_info() (py-lablib.devices.NKT.interbus.IInterbusModule method), 808

method), 734

get\_full\_info() (py-lablib.devices.NKT.interbus.InterbusSystem method), 808

method), 729

get\_full\_info() (py-lablib.devices.NKT.interbus.SuperKExtremeInterbusModule method), 815

method), 730

get\_full\_info() (py-lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule method), 821

method), 731

get\_full\_info() (py-lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule method), 821

method), 732

get\_full\_info() (py-lablib.devices.NKT.interbus.SuperKSelectInterbusModule method), 818

method), 747

get\_full\_info() (py-lablib.devices.Omron.base.OmronE5xCController method), 831

method), 750

get\_full\_info() (py-lablib.devices.Ophir.base.OphirDevice method), 836

method), 753

get\_full\_info() (py-lablib.devices.Ophir.base.VegaPowerMeter method), 850

method), 743

get\_full\_info() (py-lablib.devices.OZOptics.base.DD100 method), 850

method), 745

get\_full\_info() (py-lablib.devices.OZOptics.base.EPC04 method), 861

method), 740

get\_full\_info() (py-lablib.devices.OZOptics.base.OZOpticsDevice method), 872

method), 742

get\_full\_info() (py-lablib.devices.OZOptics.base.TF100 method), 875

get\_full\_info() (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 776

get\_full\_info() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 785

get\_full\_info() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 808

get\_full\_info() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 791

get\_full\_info() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 800

get\_full\_info() (py-lablib.devices.PhyikInstrumente.base.GenericPIController method), 815

get\_full\_info() (py-lablib.devices.PhyikInstrumente.base.PIE515 method), 821

get\_full\_info() (py-lablib.devices.PhyikInstrumente.base.PIE516 method), 818

get\_full\_info() (py-lablib.devices.PrincetonInstruments.picam.PicamCamera method), 831

get\_full\_info() (py-lablib.devices.Rigol.power\_supply.DP1116A method), 836

get\_full\_info() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera method), 850

get\_full\_info() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 845

get\_full\_info() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 861

get\_full\_info() (py-lablib.devices.SmarAct.MCS2.MCS2 method), 872

get\_full\_info() (py-lablib.devices.SmarAct.scu3d.SCU3D method), 875

<code>get_full_info()</code>	(py- lablib.devices.Standa.base.Standa8SMC method), 879	lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 908
<code>get_full_info()</code>	(py- lablib.devices.Tektronix.base.DPO2000 method), 896	<code>get_full_info()</code> (py- lablib.devices.Toptica.ibeam.TopticaIBeam method), 970
<code>get_full_info()</code>	(py- lablib.devices.Tektronix.base.ITektronixScope method), 886	<code>get_full_info()</code> (py- lablib.devices.Trinamic.base.TMCM1110 method), 975
<code>get_full_info()</code>	(py- lablib.devices.Tektronix.base.TDS2000 method), 889	<code>get_full_info()</code> (py- lablib.devices.Trinamic.base.TMCMx110 method), 977
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.elliptec.ElliptecMotor method), 915	<code>get_full_info()</code> (py- lablib.devices.uc480.uc480.UC480Camera method), 1028
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 918	<code>get_full_info()</code> (py- lablib.devices.Voltcraft.multimeter.VC7055 method), 982
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.KinesisDevice method), 922	<code>get_full_info()</code> (py- lablib.devices.Voltcraft.multimeter.VC880 method), 986
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.KinesisMotor method), 933	<code>get_full_info()</code> (py- lablib.devices.Windows.joystick.Joystick method), 988
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 940	<code>get_full_status()</code> (py- lablib.core.devio.comm_backend.ICommBackendWrapper method), 192
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 937	<code>get_full_status()</code> (py- lablib.core.devio.interface.IDevice method), 197
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 944	<code>get_full_status()</code> (py- lablib.core.devio.SCPi.SCPIDevice method), 168
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.kinesis.MFF method), 926	<code>get_full_status()</code> (py- lablib.devices.Agilent.pressure.XGS600 method), 506
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.misc.GenericPM method), 948	<code>get_full_status()</code> (py- lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 516
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.misc.PM160 method), 951	<code>get_full_status()</code> (py- lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 510
<code>get_full_info()</code> (pylablib.devices.Thorlabs.serial.FW method), 959	(py- lablib.devices.Thorlabs.serial.FWv1 method), 962	<code>get_full_status()</code> (py- lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 531
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.serial.MDT69xA method), 965	<code>get_full_status()</code> (py- lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 541
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955	<code>get_full_status()</code> (py- lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 549
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955	<code>get_full_status()</code> (py- lablib.devices.Arcus.performax.GenericPerformaxStage method), 552
<code>get_full_info()</code>	(py- lablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955	<code>get_full_status()</code> (py- lablib.devices.Arcus.performax.GenericPerformaxStage method), 552

<i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 558	<i>lablib.devices.Cryocon.base.Cryocon1x</i> method), 601
<i>get_full_status()</i> (py- <i>lablib.devices.Arcus.performax.Performax4EXStage</i> method), 555	<i>get_full_status()</i> (py- <i>lablib.devices.Cryomagnetics.base.LM500</i> method), 606
<i>get_full_status()</i> (py- <i>lablib.devices.Arcus.performax.PerformaxDMXJSASStage</i> method), 562	<i>get_full_status()</i> (py- <i>lablib.devices.Cryomagnetics.base.LM510</i> method), 609
<i>get_full_status()</i> (py- <i>lablib.devices.Arduino.base.IArduinoDevice</i> method), 565	<i>get_full_status()</i> (py- <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> method), 619
<i>get_full_status()</i> (py- <i>lablib.devices.Attocube.anc300.ANC300</i> method), 569	<i>get_full_status()</i> (py- <i>lablib.devices.ElektroAutomatik.base.PS2000B</i> method), 625
<i>get_full_status()</i> (py- <i>lablib.devices.Attocube.anc350.ANC350</i> method), 573	<i>get_full_status()</i> (py- <i>lablib.devices.HighFinesse.wlm.WLM</i> method), 629
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.generic.GenericAWG</i> method), 459	<i>get_full_status()</i> (py- <i>lablib.devices.Hubner.Cobolt.Cobolt</i> method), 632
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.Agilent33220A</i> method), 469	<i>get_full_status()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 643
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.Agilent33500</i> method), 463	<i>get_full_status()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 638
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.InstekAFG2000</i> method), 481	<i>get_full_status()</i> (py- <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> method), 659
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.InstekAFG2225</i> method), 475	<i>get_full_status()</i> (py- <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> method), 654
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.RigolDG1000</i> method), 500	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.IAttributeCamera</i> method), 998
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.RSInstekAFG21000</i> method), 488	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.IBinROICamera</i> method), 1016
<i>get_full_status()</i> (py- <i>lablib.devices.AWG.specific.TektronixAFG1000</i> method), 494	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.ICamera</i> method), 993
<i>get_full_status()</i> (py- <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> method), 582	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.IExposureCamera</i> method), 1007
<i>get_full_status()</i> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> method), 1003
<i>get_full_status()</i> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 588	<i>get_full_status()</i> (py- <i>lablib.devices.interface.camera.IROICamera</i> method), 1012
<i>get_full_status()</i> (py- <i>lablib.devices.Conrad.base.RelayBoard</i> method), 598	<i>get_full_status()</i> (py- <i>lablib.devices.interface.stage.IMultiaxisStage</i> method), 1022
<i>get_full_status()</i> (py-	<i>get_full_status()</i> (py-

`lablib.devices.interface.stage.IStage` method), 1021  
`get_full_status()` (py-lablib.devices.Keithley.multimeter.Keithley2110 method), 668  
`get_full_status()` (py-lablib.devices.KJL.base.KJL300 method), 664  
`get_full_status()` (py-lablib.devices.Lakeshore.base.Lakeshore218 method), 675  
`get_full_status()` (py-lablib.devices.Lakeshore.base.Lakeshore370 method), 679  
`get_full_status()` (py-lablib.devices.LaserQuantum.base.Finesse method), 684  
`get_full_status()` (py-lablib.devices.Leybold.base.GenericITR method), 686  
`get_full_status()` (py-lablib.devices.Leybold.base.ITR90 method), 688  
`get_full_status()` (py-lablib.devices.LighthousePhotonics.base.SproutG method), 691  
`get_full_status()` (py-lablib.devices.Lumel.base.LumelRE72Controller method), 693  
`get_full_status()` (py-lablib.devices.M2.base.ICEBlocDevice method), 697  
`get_full_status()` (pylablib.devices.M2.emm.EMM method), 700  
`get_full_status()` (py-lablib.devices.M2.solstis.Solstis method), 706  
`get_full_status()` (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 711  
`get_full_status()` (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716  
`get_full_status()` (py-lablib.devices.Newport.picomotor.Picomotor8742 method), 738  
`get_full_status()` (pylablib.devices.NI.daq.NIDAQ method), 724  
`get_full_status()` (py-lablib.devices.NKT.interbus.GenericInterbusDevice method), 726  
`get_full_status()` (py-lablib.devices.NKT.interbus.GenericInterbusModule method), 728  
`get_full_status()` (py-lablib.devices.NKT.interbus.IInterbusModule method), 728  
`get_full_status()` (py-lablib.devices.NKT.interbus.InterbusSystem method), 734  
`get_full_status()` (py-lablib.devices.NKT.interbus.SuperKExtremeInterbusModule method), 729  
`get_full_status()` (py-lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule method), 730  
`get_full_status()` (py-lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule method), 731  
`get_full_status()` (py-lablib.devices.NKT.interbus.SuperKSelectInterbusModule method), 732  
`get_full_status()` (py-lablib.devices.Omron.base.OmronE5xCCController method), 747  
`get_full_status()` (py-lablib.devices.Ophir.base.OphirDevice method), 750  
`get_full_status()` (py-lablib.devices.Ophir.base.VegaPowerMeter method), 753  
`get_full_status()` (py-lablib.devices.OZOptics.base.DD100 method), 743  
`get_full_status()` (py-lablib.devices.OZOptics.base.EPC04 method), 746  
`get_full_status()` (py-lablib.devices.OZOptics.base.OZOpticsDevice method), 740  
`get_full_status()` (py-lablib.devices.OZOptics.base.TF100 method), 742  
`get_full_status()` (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 760  
`get_full_status()` (py-lablib.devices.Pfeiffer.base.DPG202 method), 768  
`get_full_status()` (py-lablib.devices.Pfeiffer.base.TPG260 method), 766  
`get_full_status()` (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 776  
`get_full_status()` (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 785

<code>get_full_status()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlipper</i> <i>method), 808</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.BasicKinesisDevice</i> <i>method), 918</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</i> <i>method), 791</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisDevice</i> <i>method), 922</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method), 800</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> <i>method), 933</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PhysikInstrumente.base.GenericPIController</i> <i>method), 815</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoController</i> <i>method), 940</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PhysikInstrumente.base.PIE515</i> <i>method), 821</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</i> <i>method), 937</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PhysikInstrumente.base.PIE516</i> <i>method), 818</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</i> <i>method), 944</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method), 831</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.kinesis.MFF</i> <i>method), 926</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Rigol.power_supply.DP1116A</i> <i>method), 836</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.misc.GenericPM</i> <i>method), 948</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCameras</i> <i>method), 850</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.misc.PM160</i> <i>method), 951</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method), 845</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.serial.FW</i> <i>method), 959</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method), 861</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.serial.FWv1</i> <i>method), 962</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.SmarAct.MCS2.MCS2</i> <i>method), 872</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.serial.MDT69xA</i> <i>method), 965</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.SmarAct.scu3d.SC3D</i> <i>method), 875</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.serial.ThorlabsSerialInterface</i> <i>method), 955</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Standa.base.Standa8SMC</i> <i>method), 879</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method), 908</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Tektronix.base.DPO2000</i> <i>method), 896</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Toptica.ibeam.TopticaIBeam</i> <i>method), 970</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Tektronix.base.ITektronixScope</i> <i>method), 886</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Trinamic.base.TMCM1110</i> <i>method), 975</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Tektronix.base.TDS2000</i> <i>method), 889</i>	(py- <code>get_full_status()</code> <i>lablib.devices.Trinamic.base.TMCMx110</i> <i>method), 977</i>	(py-
<code>get_full_status()</code> <i>lablib.devices.Thorlabs.elliptec.ElliptecMotor</i> <i>method), 915</i>	(py- <code>get_full_status()</code> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method), 1029</i>	(py-



<code>get_full_status()</code> <i>lablib.devices.Voltcraft.mmultimeter.VC7055</i> <i>method</i> ), 982	(py-	<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 482	(py-
<code>get_full_status()</code> <i>lablib.devices.Voltcraft.mmultimeter.VC880</i> <i>method</i> ), 986	(py-	<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 476	(py-
<code>get_full_status()</code> <i>lablib.devices.Windows.joystick.Joystick</i> <i>method</i> ), 988	(py-	<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 500	(py-
<code>get_full_web_status()</code> <i>lablib.devices.M2.solstis.Solstis</i> 701	(py- <i>method</i> ),	<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 488	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 456		<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 494	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 469		<code>get_gauge_control_settings()</code> <i>lablib.devices.Pfeiffer.base.TPG260</i> <i>method</i> ), 766	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 463		<code>get_gauge_kind()</code> <i>lablib.devices.Pfeiffer.base.TPG260</i> <i>method</i> ), 765	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 481		<code>get_gen_move_parameters()</code> <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> <i>method</i> ), 931	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 476		<code>get_general_input()</code> <i>lablib.devices.Trinamic.base.TMCM1110</i> <i>method</i> ), 973	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 500		<code>get_general_input()</code> <i>lablib.devices.Trinamic.base.TMCMx110</i> <i>method</i> ), 977	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 488		<code>get_genicam_info_xml()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 800	(py-
<code>get_function()</code> ( <i>pylablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 494		<code>get_genicam_info_xml()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 850	(py-
<code>get_function()</code> ( <i>pylablib.devices.Keithley.mmultimeter.Keithley2110</i> <i>method</i> ), 666		<code>get_genicam_info_xml()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method</i> ), 842	(py-
<code>get_function()</code> ( <i>pylablib.devices.Voltcraft.mmultimeter.VC7055</i> <i>method</i> ), 981		<code>get_global_parameter()</code> <i>lablib.devices.Trinamic.base.TMCM1110</i> <i>method</i> ), 972	(py-
<code>get_function_parameters()</code> <i>lablib.devices.Keithley.mmultimeter.Keithley2110</i> <i>method</i> ), 667	(py-	<code>get_global_parameter()</code> <i>lablib.devices.Trinamic.base.TMCMx110</i> <i>method</i> ), 977	(py-
<code>get_gain()</code> ( <i>pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 905		<code>get_global_speed()</code> <i>lablib.devices.Arcus.performax.Performax2EXStage</i> <i>method</i> ), 558	(py-
<code>get_gain_boost()</code> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1026	(py-	<code>get_global_speed()</code> <i>lablib.devices.Arcus.performax.Performax4EXStage</i> <i>method</i> ), 554	(py-
<code>get_gain_range()</code> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 905	(py-	<code>get_grabber_attribute()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1001	(py-
<code>get_gains()</code> ( <i>pylablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1026			
<code>get_gate_polarity()</code> <i>lablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 458	(py-		
<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 469	(py-		
<code>get_gate_polarity()</code> <i>lablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 463	(py-		

<code>get_grabber_attribute()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 800	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 801	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 801
<code>get_grabber_attribute()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850
<code>get_grabber_attribute()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 845	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842	(py- <code>get_grabber_detector_size()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842
<code>get_grabber_attribute_value()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516	(py- <code>get_grabber_roi()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516	(py- <code>get_grabber_roi()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516
<code>get_grabber_attribute_value()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 643	(py- <code>get_grabber_roi()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593	(py- <code>get_grabber_roi()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593
<code>get_grabber_attribute_value()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 634	(py- <code>get_grabber_roi()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586	(py- <code>get_grabber_roi()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586
<code>get_grabber_attribute_value()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> method), 1001	(py- <code>get_grabber_roi()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 643	(py- <code>get_grabber_roi()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 643
<code>get_grabber_attribute_value()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 791	(py- <code>get_grabber_roi()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635	(py- <code>get_grabber_roi()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635
<code>get_grabber_attribute_value()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 800	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> method), 808	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> method), 808
<code>get_grabber_attribute_value()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 791	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 791
<code>get_grabber_attribute_value()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 845	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 801	(py- <code>get_grabber_roi()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 801
<code>get_grabber_detector_size()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516	(py- <code>get_grabber_roi()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850	(py- <code>get_grabber_roi()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 850
<code>get_grabber_detector_size()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593	(py- <code>get_grabber_roi()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842	(py- <code>get_grabber_roi()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842
<code>get_grabber_detector_size()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 516
<code>get_grabber_detector_size()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 643	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593
<code>get_grabber_detector_size()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 634	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586
<code>get_grabber_detector_size()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> method), 808	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 644	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 644
<code>get_grabber_detector_size()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 791	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635	(py- <code>get_grabber_roi_limits()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635

`get_grabber_roi_limits()` (py- `get_handler()` (pylablib.core.gui.value\_handling.PushButtonValueHandler), 821  
 lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowController, 821  
 method), 808 `get_handler()` (pylablib.core.gui.value\_handling.StandardValueHandler  
 method), 315  
`get_grabber_roi_limits()` (py- `get_handler()` (pylablib.core.gui.value\_handling.ToolButtonValueHandler), 322  
 lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusH4000, 322  
 method), 792 `get_handler()` (pylablib.core.gui.value\_handling.VirtualValueHandler  
 method), 313  
`get_grabber_roi_limits()` (py- `get_handler()` (pylablib.core.gui.widgets.container.IQContainer  
 lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera, 313  
 method), 801 `get_handler()` (pylablib.core.gui.widgets.container.IQWidgetContainer  
 method), 237  
`get_grabber_roi_limits()` (py- `get_handler()` (pylablib.core.gui.widgets.container.QContainer  
 lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber, 239  
 method), 851 `get_handler()` (pylablib.core.gui.widgets.container.QDialogContainer  
 method), 243  
`get_grabber_roi_limits()` (py- `get_handler()` (pylablib.core.gui.widgets.container.QContainer  
 lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber, 239  
 method), 843 `get_handler()` (pylablib.core.gui.widgets.container.QDialogContainer  
 method), 257  
`get_grating()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph), 257  
 method), 545 `get_handler()` (pylablib.core.gui.widgets.container.QFrameContainer  
 method), 252  
`get_grating_info()` (py- `get_handler()` (pylablib.core.gui.widgets.container.QGroupBoxContainer), 262  
 lablib.devices.Andor.Shamrock.ShamrockSpectrograph, 262  
 method), 545 `get_handler()` (pylablib.core.gui.widgets.container.QScrollAreaContainer), 270  
 method), 546 `get_handler()` (pylablib.core.gui.widgets.container.QScrollAreaContainer), 267  
`get_gratings_number()` (py- `get_handler()` (pylablib.core.gui.widgets.container.QTabContainer  
 lablib.devices.Andor.Shamrock.ShamrockSpectrograph, 267  
 method), 545 `get_handler()` (pylablib.core.gui.widgets.container.QWidgetContainer  
 method), 248  
`get_gui_controller()` (in module py- `get_handler()` (pylablib.core.gui.widgets.param\_table.ParamTable  
 lablib.core.thread.controller), 363 method), 293  
`get_gui_thread()` (in module py- `get_handler()` (pylablib.core.gui.widgets.param\_table.StatusTable  
 lablib.core.thread.threadprop), 370 method), 304  
`get_gui_values()` (in module py- `get_handler()` (pylablib.core.gui.widgets.param\_table.StatusTable  
 lablib.core.gui.value\_handling), 329 method), 304  
`get_handle()` (pylablib.devices.Basler.pylon.BaslerPylonCameraBufferAndGen), 579 (py-  
 method), 579 lablib.devices.Attocube.anc350.ANC350  
`get_handler()` (pylablib.core.gui.value\_handling.CheckboxValueHandler), 570  
 method), 320 `get_hblanking()` (py-  
`get_handler()` (pylablib.core.gui.value\_handling.ComboBoxValueHandler), 709  
 method), 323 lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera  
 method), 709  
`get_handler()` (pylablib.core.gui.value\_handling.GUIValueHandler), 327 (py-  
 method), 327 lablib.devices.Ophir.base.VegaPowerMeter  
`get_handler()` (pylablib.core.gui.value\_handling.IBoolValueHandler), 751  
 method), 319 `get_head_info()` (py-  
`get_handler()` (pylablib.core.gui.value\_handling.ISingleValueHandler), 630  
 method), 316 lablib.devices.Hubner.Cobolt.Cobolt method),  
`get_handler()` (pylablib.core.gui.value\_handling.IValueHandler), 605  
 method), 312 `get_help()` (pylablib.devices.PhysikInstrumente.base.GenericPIController  
 method), 815  
`get_handler()` (pylablib.core.gui.value\_handling.LabelValueHandler), 818 (pylablib.devices.PhysikInstrumente.base.PIE516  
 method), 318 method), 818  
`get_handler()` (pylablib.core.gui.value\_handling.LineEditValueHandler), 605  
 method), 317 lablib.devices.Cryomagnetics.base.LM500  
`get_handler()` (pylablib.core.gui.value\_handling.ProgressBarValueHandler), 605  
 method), 324 `get_high_level()` (py-  
`get_handler()` (pylablib.core.gui.value\_handling.PropertyValueHandler), 609  
 method), 314 lablib.devices.Cryomagnetics.base.LM510  
 method), 609



- `get_home_offset()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 914
- `get_home_parameters()` (pylablib.devices.Trinamic.base.TMCM1110 method), 974
- `get_home_parameters()` (pylablib.devices.Trinamic.base.TMCMx110 method), 977
- `get_homing_parameters()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 931
- `get_horizontal_offset()` (pylablib.devices.Tektronix.base.DPO2000 method), 896
- `get_horizontal_offset()` (pylablib.devices.Tektronix.base.ITektronixScope method), 883
- `get_horizontal_offset()` (pylablib.devices.Tektronix.base.TDS2000 method), 890
- `get_horizontal_span()` (pylablib.devices.Tektronix.base.DPO2000 method), 896
- `get_horizontal_span()` (pylablib.devices.Tektronix.base.ITektronixScope method), 883
- `get_horizontal_span()` (pylablib.devices.Tektronix.base.TDS2000 method), 890
- `get_hsspeed()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 525
- `get_hsspeed_frequency()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 525
- `get_id()` (pylablib.core.devio.SCPI.SCPIDevice method), 166
- `get_id()` (pylablib.devices.AWG.generic.GenericAWG method), 459
- `get_id()` (pylablib.devices.AWG.specific.Agilent33220A method), 469
- `get_id()` (pylablib.devices.AWG.specific.Agilent33500 method), 463
- `get_id()` (pylablib.devices.AWG.specific.InstekAFG2000 method), 482
- `get_id()` (pylablib.devices.AWG.specific.InstekAFG2225 method), 476
- `get_id()` (pylablib.devices.AWG.specific.RigolDG1000 method), 500
- `get_id()` (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 488
- `get_id()` (pylablib.devices.AWG.specific.TektronixAFG1000 method), 494
- `get_id()` (pylablib.devices.Cryocon.base.Cryocon1x method), 601
- `get_id()` (pylablib.devices.Cryomagnetics.base.LM500 method), 606
- `get_id()` (pylablib.devices.Cryomagnetics.base.LM510 method), 609
- `get_id()` (pylablib.devices.Keithley.multimeter.Keithley2110 method), 669
- `get_id()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 675
- `get_id()` (pylablib.devices.Lakeshore.base.Lakeshore370 method), 679
- `get_id()` (pylablib.devices.Newport.picomotor.Picomotor8742 method), 736
- `get_id()` (pylablib.devices.PhysikInstrumente.base.GenericPIController method), 815
- `get_id()` (pylablib.devices.PhysikInstrumente.base.PIE515 method), 821
- `get_id()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 818
- `get_id()` (pylablib.devices.Rigol.power\_supply.DP1116A method), 836
- `get_id()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 861
- `get_id()` (pylablib.devices.Tektronix.base.DPO2000 method), 896
- `get_id()` (pylablib.devices.Tektronix.base.ITektronixScope method), 886
- `get_id()` (pylablib.devices.Tektronix.base.TDS2000 method), 890
- `get_id()` (pylablib.devices.Thorlabs.misc.GenericPM method), 948
- `get_id()` (pylablib.devices.Thorlabs.misc.PM160 method), 951
- `get_id()` (pylablib.devices.Thorlabs.serial.FW method), 959
- `get_id()` (pylablib.devices.Thorlabs.serial.FWv1 method), 962
- `get_id()` (pylablib.devices.Thorlabs.serial.MDT69xA method), 965
- `get_id()` (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955
- `get_id()` (pylablib.devices.Voltcraft.multimeter.VC7055 method), 982
- `get_imag_part_ft()` (in module pylablib.core.dataproc.fourier), 147
- `get_image_indexing()` (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 517
- `get_image_indexing()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 511
- `get_image_indexing()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 531

<code>get_image_indexing()</code> <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 541	(py-	<code>get_image_indexing()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 785	(py-
<code>get_image_indexing()</code> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 582	(py-	<code>get_image_indexing()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa</i> <i>method</i> ), 809	(py-
<code>get_image_indexing()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 593	(py-	<code>get_image_indexing()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam</i> <i>method</i> ), 792	(py-
<code>get_image_indexing()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 588	(py-	<code>get_image_indexing()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame</i> <i>method</i> ), 801	(py-
<code>get_image_indexing()</code> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 619	(py-	<code>get_image_indexing()</code> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 831	(py-
<code>get_image_indexing()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 644	(py-	<code>get_image_indexing()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 851	(py-
<code>get_image_indexing()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 639	(py-	<code>get_image_indexing()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb</i> <i>method</i> ), 845	(py-
<code>get_image_indexing()</code> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 659	(py-	<code>get_image_indexing()</code> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 908	(py-
<code>get_image_indexing()</code> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 654	(py-	<code>get_image_indexing()</code> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1029	(py-
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 998	(py-	<code>get_image_mode_parameters()</code> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 529	(py-
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1016	(py-	<code>get_imported_modules()</code> (in module <i>py-</i> <i>lablib.core.utils.module</i> ), 438	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 991	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.Array1DWrapper</i> <i>method</i> ), 154	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1007	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.Array2DWrapper</i> <i>method</i> ), 159	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1003	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.DataFrame2DWrapper</i> <i>method</i> ), 160	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1012	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.I1DWrapper</i> <i>method</i> ), 153	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1003	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.I2DWrapper</i> <i>method</i> ), 156	
<code>get_image_indexing()</code> <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1012	(py-	<code>get_index()</code> ( <i>pylablib.core.dataproc.table_wrap.Series1DWrapper</i> <i>method</i> ), 155	
<code>get_image_indexing()</code> <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 711	(py-	<code>get_index_by_name()</code> (py- <i>lablib.core.gui.widgets.container.QTabContainer</i> <i>method</i> ), 272	
<code>get_image_indexing()</code> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 760	(py-	<code>get_index_values()</code> (py- <i>lablib.core.gui.widgets.button_selector.ButtonSelector</i> <i>method</i> ), 233	
<code>get_image_indexing()</code> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 776	(py-	<code>get_index_values()</code> (py- <i>lablib.core.gui.widgets.combo_box.ComboBox</i> <i>method</i> ), 234	
		<code>get_indicator()</code> (py-	

`lablib.core.gui.value_handling.GUIValues`  
`method`), 329

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.IQContainer`  
`method`), 238

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.IQWidgetContainer`  
`method`), 243

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QContainer`  
`method`), 240

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QDialogContainer`  
`method`), 257

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QFrameContainer`  
`method`), 253

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QGroupBoxContainer`  
`method`), 262

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer`  
`method`), 270

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QLabelWidget`  
`method`), 267

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QTabContainer`  
`method`), 273

`get_indicator()` (py-  
`lablib.core.gui.widgets.container.QWidgetContainer`  
`method`), 248

`get_indicator()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable`  
`method`), 292

`get_indicator()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable`  
`method`), 304

`get_indicator_widget()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable`  
`method`), 292

`get_indicator_widget()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable`  
`method`), 304

`get_input_channels()` (py-  
`lablib.devices.NI.daq.NIDAQ` `method`), 720

`get_inserted()` (pylablib.core.dataproc.table\_wrap.Array1DWrapper.  
`method`), 153

`get_inserted()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper.  
`method`), 157

`get_inserted()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper.  
`method`), 159

`get_inserted()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper.  
`method`), 159

`get_inserted()` (pylablib.core.dataproc.table\_wrap.Series1DWrapper.  
`method`), 155

`get_interlock()` (py-  
`lablib.devices.Hubner.Cobolt.Cobolt` `method`),  
 631

`get_interlock_status()` (py-  
`lablib.devices.LaserQuantum.base.Finesse`  
`method`), 683

`get_interlock_status()` (py-  
`lablib.devices.LighthousePhotonics.base.SproutG`  
`method`), 690

`get_internal_buffer_status()` (py-  
`lablib.devices.PCO.SC2.PCOSC2Camera`  
`method`), 757

`get_interval()` (pylablib.devices.Cryomagnetics.base.LM500  
`method`), 605

`get_interval()` (pylablib.devices.Cryomagnetics.base.LM510  
`method`), 610

`get_iris_width()` (py-  
`lablib.devices.Andor.Shamrock.ShamrockSpectrograph`  
`method`), 548

`get_jog_parameters()` (py-  
`lablib.devices.Thorlabs.kinesis.KinesisMotor`  
`method`), 930

`get_jog_parameters()` (py-  
`lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor`  
`method`), 936

`get_kcube_trigio_parameters()` (py-  
`lablib.devices.Thorlabs.kinesis.KinesisMotor`  
`method`), 931

`get_kcube_trigpos_parameters()` (py-  
`lablib.devices.Thorlabs.kinesis.KinesisMotor`  
`method`), 931

`get_keepclean_time()` (py-  
`lablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`method`), 528

`get_kernel()` (in module py-  
`lablib.core.dataproc.feature`), 136

`get_kernel_func()` (in module py-  
`lablib.core.dataproc.specfunc`), 151

`get_key_switch()` (py-  
`lablib.devices.Hubner.Cobolt.Cobolt` `method`),  
 631

`get_kinetic_mode_parameters()` (py-  
`lablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`method`), 527

`get_label_widget()` (py-  
`lablib.core.gui.widgets.param_table.ParamTable`  
`method`), 293

`get_label_widget()` (py-  
`lablib.core.gui.widgets.param_table.StatusTable`  
`method`), 304

`get_laser_status()` (`pylablib.devices.M2.emm.EMM` method), 698  
`get_last_filled_column()` (in module `pylablib.core.gui.utils`), 310  
`get_last_filled_row()` (in module `pylablib.core.gui.utils`), 310  
`get_last_home_position()` (`pylablib.devices.Trinamic.base.TMCM1110` method), 974  
`get_last_home_position()` (`pylablib.devices.Trinamic.base.TMCMx110` method), 977  
`get_last_read_frequency()` (`pylablib.devices.Sirah.tuner.MatisseTuner` method), 865  
`get_last_report()` (`pylablib.devices.M2.base.ICEBlocDevice` method), 696  
`get_last_report()` (`pylablib.devices.M2.emm.EMM` method), 700  
`get_last_report()` (`pylablib.devices.M2.solstis.Solstis` method), 706  
`get_layout_container()` (in module `pylablib.core.gui.utils`), 309  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.IQWidgetContainer` method), 243  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 257  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.QFrameContainer` method), 253  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer` method), 262  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainer` method), 267  
`get_layout_shape()` (`pylablib.core.gui.widgets.container.QWidgetContainer` method), 248  
`get_layout_shape()` (`pylablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget` method), 281  
`get_layout_shape()` (`pylablib.core.gui.widgets.layout_manager.QLayoutManagedWidget` method), 282  
`get_layout_shape()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 294  
`get_layout_shape()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 294  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.IQWidgetContainer` method), 243  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 257  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.QFrameContainer` method), 253  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer` method), 262  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainer` method), 267  
`get_layout_tags()` (`pylablib.core.gui.widgets.container.QWidgetContainer` method), 248  
`get_layout_tags()` (`pylablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget` method), 280  
`get_layout_tags()` (`pylablib.core.gui.widgets.layout_manager.QLayoutManagedWidget` method), 283  
`get_layout_tags()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 294  
`get_layout_tags()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 304  
`get_level()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 605  
`get_level()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 610  
`get_library_name()` (in module `pylablib.core.utils.module`), 438  
`get_library_path()` (in module `pylablib.core.utils.module`), 438  
`get_limit_switch_parameters()` (`pylablib.devices.Thorlabs.kinesis.KinesisMotor` method), 931  
`get_limit_switches_parameters()` (`pylablib.devices.Trinamic.base.TMCM1110` method), 973  
`get_limit_switches_parameters()` (`pylablib.devices.Trinamic.base.TMCMx110` method), 977  
`get_limit_switches_state()` (`pylablib.devices.Trinamic.base.TMCM1110` method), 974  
`get_limit_switches_state()` (`pylablib.devices.Trinamic.base.TMCMx110` method), 977

<code>get_load()</code> ( <code>pylablib.devices.AWG.generic.GenericAWG</code> method), 456	<code>lablib.core.utils.dictionary.DictionaryPointer</code> method), 389
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.Agilent33220A</code> method), 470	<code>get_matching_paths()</code> ( <code>pylablib.core.utils.dictionary.FilterTree</code> method), 406
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.Agilent33500</code> method), 463	<code>get_matching_paths()</code> ( <code>pylablib.core.utils.dictionary.PrefixTree</code> method), 398
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2000</code> method), 482	<code>get_matching_subtree()</code> ( <code>pylablib.core.utils.dictionary.Dictionary</code> method), 384
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2225</code> method), 476	<code>get_matching_subtree()</code> ( <code>pylablib.core.utils.dictionary.DictionaryPointer</code> method), 389
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.RigolDG1000</code> method), 500	<code>get_matching_subtree()</code> ( <code>pylablib.core.utils.dictionary.FilterTree</code> method), 406
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.RSInstekAFG21000</code> method), 488	<code>get_matching_subtree()</code> ( <code>pylablib.core.utils.dictionary.PrefixTree</code> method), 398
<code>get_load()</code> ( <code>pylablib.devices.AWG.specific.TektronixAFG1000</code> method), 494	<code>get_max_attenuation()</code> ( <code>pylablib.devices.OZOptics.base.DD100</code> method), 743
<code>get_loaded_package_modules()</code> (in module <code>pylablib.core.utils.module</code> ), 437	<code>get_max_gains()</code> ( <code>pylablib.devices.uc480.uc480.UC480Camera</code> method), 1026
<code>get_local_addr()</code> (in module <code>pylablib.core.utils.net</code> ), 440	<code>get_max_output_current()</code> ( <code>pylablib.devices.Hubner.Cobolt.Cobolt</code> method), 631
<code>get_local_hostname()</code> (in module <code>pylablib.core.utils.net</code> ), 441	<code>get_max_output_power()</code> ( <code>pylablib.devices.Hubner.Cobolt.Cobolt</code> method), 631
<code>get_local_name()</code> ( <code>pylablib.core.utils.net.ClientSocket</code> method), 442	<code>get_max_prefix()</code> ( <code>pylablib.core.utils.dictionary.Dictionary</code> method), 378
<code>get_location()</code> (in module <code>pylablib.core.fileio.location</code> ), 222	<code>get_max_prefix()</code> ( <code>pylablib.core.utils.dictionary.DictionaryPointer</code> method), 389
<code>get_low_level()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 605	<code>get_max_prefix()</code> ( <code>pylablib.core.utils.dictionary.FilterTree</code> method), 406
<code>get_low_level()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 610	<code>get_max_prefix()</code> ( <code>pylablib.core.utils.dictionary.PrefixTree</code> method), 398
<code>get_mandatory_args()</code> ( <code>pylablib.core.dataproc.callable.FunctionCallable</code> method), 132	<code>get_max_vsspeed()</code> ( <code>pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 525
<code>get_mandatory_args()</code> ( <code>pylablib.core.dataproc.callable.ICallable</code> method), 130	<code>get_measurement_filter()</code> ( <code>pylablib.devices.Pfeiffer.base.TPG260</code> method), 765
<code>get_mandatory_args()</code> ( <code>pylablib.core.dataproc.callable.JoinedCallable</code> method), 131	<code>get_measurement_interval()</code> ( <code>pylablib.devices.HighFinesse.wlm.WLM</code> method), 628
<code>get_mandatory_args()</code> ( <code>pylablib.core.dataproc.callable.MethodCallable</code> method), 133	<code>get_measurement_rate()</code> ( <code>pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector</code> method), 943
<code>get_mandatory_args()</code> ( <code>pylablib.core.dataproc.callable.MultiplexedCallable</code> method), 130	
<code>get_manual_output()</code> ( <code>pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector</code> method), 943	
<code>get_matching_paths()</code> ( <code>pylablib.core.utils.dictionary.Dictionary</code> method), 384	
<code>get_matching_paths()</code> ( <code>pylablib.core.utils.dictionary.FilterTree</code> method), 406	



<code>lablib.devices.Voltcraft.multimeter.VC7055</code> (method), 981	<code>get_motor_type()</code> (py- <code>lablib.devices.Newport.picomotor.Picomotor8742</code> method), 737
<code>get_measurementf()</code> (py- <code>lablib.devices.Lumel.base.LumelRE72Controller</code> method), 692	<code>get_move_parameters()</code> (py- <code>lablib.devices.Standa.base.Standa8SMC</code> method), 879
<code>get_measurementi()</code> (py- <code>lablib.devices.Lumel.base.LumelRE72Controller</code> method), 693	<code>get_multi_track_mode_parameters()</code> (py- <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 529
<code>get_measurementi()</code> (py- <code>lablib.devices.Omron.base.OmronE5xCController</code> method), 747	<code>get_name_by_index()</code> (py- <code>lablib.core.gui.widgets.container.QTabContainer</code> method), 272
<code>get_metadata_mode()</code> (py- <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> method), 759	<code>get_names()</code> ( <code>pylablib.core.dataproc.table_wrap.Array2DWrapper.Column</code> method), 158
<code>get_method_kind()</code> (in module <code>py- lablib.core.gui.value_handling</code> ), 311	<code>get_names()</code> ( <code>pylablib.core.dataproc.table_wrap.DataFrame2DWrapper.C</code> method), 160
<code>get_microstep_resolution()</code> (py- <code>lablib.devices.Trinamic.base.TMCM1110</code> method), 973	<code>get_nbuff()</code> ( <code>pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</code> method), 657
<code>get_microstep_resolution()</code> (py- <code>lablib.devices.Trinamic.base.TMCMx110</code> method), 977	<code>get_nbuff()</code> ( <code>pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.Callbac</code> method), 652
<code>get_min_attenuation()</code> (py- <code>lablib.devices.OZOptics.base.DD100</code> method), 743	<code>get_new_frames_range()</code> (py- <code>lablib.devices.interface.camera.FrameCounter</code> method), 994
<code>get_min_shutter_times()</code> (py- <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 526	<code>get_new_images_range()</code> (py- <code>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</code> method), 517
<code>get_missed_frames_status()</code> (py- <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> method), 540	<code>get_new_images_range()</code> (py- <code>lablib.devices.AlliedVision.Bonito.IBonitoCamera</code> method), 511
<code>get_mode()</code> ( <code>pylablib.devices.Attocube.anc300.ANC300</code> method), 567	<code>get_new_images_range()</code> (py- <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 531
<code>get_mode()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 605	<code>get_new_images_range()</code> (py- <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> method), 542
<code>get_mode()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 610	<code>get_new_images_range()</code> (py- <code>lablib.devices.Basler.pylon.BaslerPylonCamera</code> method), 582
<code>get_mode()</code> ( <code>pylablib.devices.OZOptics.base.EPC04</code> method), 745	<code>get_new_images_range()</code> (py- <code>lablib.devices.BitFlow.BitFlow.BitFlowCamera</code> method), 593
<code>get_mode_parameters()</code> (py- <code>lablib.devices.BitFlow.BitFlow.CameraFileEditor</code> method), 596	<code>get_new_images_range()</code> (py- <code>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</code> method), 589
<code>get_modulation_power_setpoint()</code> (py- <code>lablib.devices.Hubner.Cobolt.Cobolt</code> method), 632	<code>get_new_images_range()</code> (py- <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> method), 619
<code>get_module_status()</code> (py- <code>lablib.devices.SmarAct.MCS2.MCS2</code> method), 870	<code>get_new_images_range()</code> (py- <code>lablib.devices.IMAQ.IMAQ.IMAQCamera</code> method), 644
<code>get_module_status_n()</code> (py- <code>lablib.devices.SmarAct.MCS2.MCS2</code> method), 870	<code>get_new_images_range()</code> (py- <code>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</code> method), 639
<code>get_motor_info()</code> (py- <code>lablib.devices.Thorlabs.elliptec.ElliptecMotor</code> method), 913	<code>get_new_images_range()</code> (py-

<code>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</code> method), 659	<code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> method), 909
<code>get_new_images_range()</code> (py- <code>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</code> method), 654	<code>get_new_images_range()</code> (py- <code>lablib.devices.uc480.uc480.UC480Camera</code> method), 1029
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.IAttributeCamera</code> method), 998	<code>get_noise_filter_mode()</code> (py- <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> method), 758
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.IBinROICamera</code> method), 1017	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Cryocon.base.Cryocon1x</code> method), 600
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.ICamera</code> method), 992	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.BasicKinesisDevice</code> method), 918
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.IExposureCamera</code> method), 1007	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisDevice</code> method), 922
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.IGrabberAttributeCamera</code> method), 1003	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisMotor</code> method), 933
<code>get_new_images_range()</code> (py- <code>lablib.devices.interface.camera.IROICamera</code> method), 1012	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisPiezoController</code> method), 940
<code>get_new_images_range()</code> (py- <code>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</code> method), 711	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</code> method), 937
<code>get_new_images_range()</code> (py- <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> method), 760	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</code> method), 944
<code>get_new_images_range()</code> (py- <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> method), 777	<code>get_number_of_channels()</code> (py- <code>lablib.devices.Thorlabs.kinesis.MFF</code> method), 926
<code>get_new_images_range()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> method), 785	<code>get_number_pixels()</code> (py- <code>lablib.devices.Andor.Shamrock.ShamrockSpectrograph</code> method), 548
<code>get_new_images_range()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 809	<code>get_oamp()</code> (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 525
<code>get_new_images_range()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQdxCamera</code> method), 792	<code>get_oamp_desc()</code> (py- <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 525
<code>get_new_images_range()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> method), 801	<code>get_ocp_threshold()</code> (py- <code>lablib.devices.ElektroAutomatik.base.PS2000B</code> method), 624
<code>get_new_images_range()</code> (py- <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> method), 831	<code>get_ocp_threshold()</code> (py- <code>lablib.devices.Rigol.power_supply.DP1116A</code> method), 835
<code>get_new_images_range()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 851	<code>get_offset()</code> (pylablib.devices.Attocube.anc300.ANC300 method), 567
<code>get_new_images_range()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 845	<code>get_offset()</code> (pylablib.devices.Attocube.anc350.ANC350 method), 572
<code>get_new_images_range()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 845	<code>get_offset()</code> (pylablib.devices.AWG.generic.GenericAWG method), 456
<code>get_new_images_range()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 845	<code>get_offset()</code> (pylablib.devices.AWG.specific.Agilent33220A method), 470

`get_offset()` (`pylablib.devices.AWG.specific.Agilent33500` method), 463  
`get_offset()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 482  
`get_offset()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 474  
`get_offset()` (`pylablib.devices.AWG.specific.RigolDG1000` method), 500  
`get_offset()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 486  
`get_offset()` (`pylablib.devices.AWG.specific.TektronixAFG61000` method), 494  
`get_opened_num()` (`pylablib.devices.Andor.AndorSDK2.LibraryController` method), 522  
`get_opened_num()` (`pylablib.devices.Andor.AndorSDK3.LibraryController` method), 534  
`get_opened_num()` (`pylablib.devices.Andor.Shamrock.LibraryController` method), 544  
`get_opened_num()` (`pylablib.devices.Basler.pylon.LibraryController` method), 574  
`get_opened_num()` (`pylablib.devices.DCAM.DCAM.LibraryController` method), 613  
`get_opened_num()` (`pylablib.devices.Mightex.MightexSSeries.LibraryController` method), 707  
`get_opened_num()` (`pylablib.devices.Photometrics.pvcam.LibraryController` method), 769  
`get_opened_num()` (`pylablib.devices.PhotonFocus.PhotonFocus.LibraryController` method), 779  
`get_opened_num()` (`pylablib.devices.PrincetonInstruments.picam.LibraryController` method), 824  
`get_opened_num()` (`pylablib.devices.SmarAct.MCS2.LibraryController` method), 868  
`get_opened_num()` (`pylablib.devices.SmarAct.scu3d.LibraryController` method), 873  
`get_opened_num()` (`pylablib.devices.Thorlabs.TLCamera.LibraryController` method), 902  
`get_opened_num()` (`pylablib.devices.utils.load_lib.LibraryController` method), 1033  
`get_operating_mode()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 630  
`get_operation_mode()` (`pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector` method), 943  
`get_optical_parameters()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 545  
`get_options()` (`pylablib.core.gui.widgets.button_selector.ButtonSelector` method), 233  
`get_options()` (`pylablib.core.gui.widgets.combo_box.ComboBox` method), 234  
`get_options_dict()` (`pylablib.core.gui.widgets.button_selector.ButtonSelector` method), 233  
`get_options_dict()` (`pylablib.core.gui.widgets.combo_box.ComboBox` method), 235  
`get_os_lib_folder()` (in module `pylablib.devices.utils.load_lib`), 1032  
`get_output()` (`pylablib.devices.Attocube.anc300.ANC300` method), 567  
`get_output_current()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 631  
`get_output_current_setpoint()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 631  
`get_output_format()` (in module `pylablib.core.fileio.savefile`), 228  
`get_output_limits()` (`pylablib.devices.ElektroAutomatik.base.PS2000B` method), 623  
`get_output_mode()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 631  
`get_output_mode()` (`pylablib.devices.LighthousePhotonics.base.SproutG` method), 690  
`get_output_parameters()` (`pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector` method), 943  
`get_output_polarity()` (`pylablib.devices.AWG.generic.GenericAWG` method), 456  
`get_output_polarity()` (`pylablib.devices.AWG.specific.Agilent33220A` method), 470  
`get_output_polarity()` (`pylablib.devices.AWG.specific.Agilent33500` method), 464  
`get_output_polarity()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 482  
`get_output_polarity()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 482



- method*), 476
- `get_output_polarity()` (*py-lablib.devices.AWG.specific.RigolDG1000 method*), 500
- `get_output_polarity()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000 method*), 488
- `get_output_polarity()` (*py-lablib.devices.AWG.specific.TektronixAFG1000 method*), 494
- `get_output_power()` (*py-lablib.devices.Hubner.Cobolt.Cobolt method*), 631
- `get_output_power()` (*py-lablib.devices.LaserQuantum.base.Finesse method*), 683
- `get_output_power()` (*py-lablib.devices.LighthousePhotonics.base.SproutG method*), 691
- `get_output_power()` (*py-lablib.devices.Toptica.ibeam.TopicalBeam method*), 969
- `get_output_power_setpoint()` (*py-lablib.devices.Hubner.Cobolt.Cobolt method*), 631
- `get_output_range()` (*py-lablib.devices.AWG.generic.GenericAWG method*), 456
- `get_output_range()` (*py-lablib.devices.AWG.specific.Agilent33220A method*), 470
- `get_output_range()` (*py-lablib.devices.AWG.specific.Agilent33500 method*), 464
- `get_output_range()` (*py-lablib.devices.AWG.specific.InstekAFG2000 method*), 482
- `get_output_range()` (*py-lablib.devices.AWG.specific.InstekAFG2225 method*), 476
- `get_output_range()` (*py-lablib.devices.AWG.specific.RigolDG1000 method*), 500
- `get_output_range()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000 method*), 488
- `get_output_range()` (*py-lablib.devices.AWG.specific.TektronixAFG1000 method*), 494
- `get_output_range()` (*py-lablib.devices.Rigol.power\_supply.DP1116A method*), 834
- `get_output_setpoint()` (*py-lablib.devices.LaserQuantum.base.Finesse method*), 683
- `get_output_setpoint()` (*py-lablib.devices.LighthousePhotonics.base.SproutG method*), 691
- `get_output_status()` (*py-lablib.devices.LaserQuantum.base.Finesse method*), 683
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.generic.GenericAWG method*), 458
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.Agilent33220A method*), 470
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.Agilent33500 method*), 464
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.InstekAFG2000 method*), 482
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.InstekAFG2225 method*), 476
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.RigolDG1000 method*), 501
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000 method*), 488
- `get_output_trigger_slope()` (*py-lablib.devices.AWG.specific.TektronixAFG1000 method*), 495
- `get_output_voltage()` (*py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method*), 939
- `get_outputf()` (*pylablib.devices.Lumel.base.LumelRE72Controller method*), 692
- `get_ovp_threshold()` (*py-lablib.devices.ElektroAutomatik.base.PS2000B method*), 624
- `get_ovp_threshold()` (*py-lablib.devices.Rigol.power\_supply.DP1116A method*), 835
- `get_package_version()` (*in module py-lablib.core.utils.module*), 437
- `get_path()` (*pylablib.core.fileio.location.LocationName method*), 217
- `get_path()` (*pylablib.core.utils.dictionary.Dictionary method*), 383
- `get_path()` (*pylablib.core.utils.dictionary.DictionaryPointer method*), 386
- `get_path()` (*pylablib.core.utils.dictionary.FilterTree method*), 406
- `get_path()` (*pylablib.core.utils.dictionary.PrefixTree method*), 398

<code>get_pcount()</code> ( <i>pylablib.devices.Thorlabs.serial.FW</i> <i>method</i> ), 958	<code>lablib.devices.Sirah.Matisse.SirahMatisse</code> <i>method</i> ), 859
<code>get_pcount()</code> ( <i>pylablib.devices.Thorlabs.serial.FWv1</i> <i>method</i> ), 961	<code>get_piezoet_position()</code> ( <i>py-</i> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method</i> ), 859
<code>get_peakdet_kernel()</code> ( <i>in module py-</i> <i>lablib.core.dataproc.feature</i> ), 136	<code>get_pixel_clock()</code> ( <i>py-</i> <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 709
<code>get_peer_args()</code> ( <i>pylablib.core.utils.ipc.IIPCCChannel</i> <i>method</i> ), 435	<code>get_pixel_correction_parameters()</code> ( <i>py-</i> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 905
<code>get_peer_args()</code> ( <i>py-</i> <i>lablib.core.utils.ipc.PipeIPCCChannel method</i> ), 435	<code>get_pixel_distance()</code> ( <i>py-</i> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 773
<code>get_peer_args()</code> ( <i>py-</i> <i>lablib.core.utils.ipc.SharedMemIPCCChannel</i> <i>method</i> ), 436	<code>get_pixel_rate()</code> ( <i>py-</i> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 757
<code>get_peer_args()</code> ( <i>py-</i> <i>lablib.core.utils.ipc.SharedMemIPCTable</i> <i>method</i> ), 437	<code>get_pixel_rate()</code> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1025
<code>get_peer_name()</code> ( <i>pylablib.core.utils.net.ClientSocket</i> <i>method</i> ), 442	<code>get_pixel_rates_range()</code> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1025
<code>get_pending()</code> ( <i>pylablib.core.devio.comm_backend.HIDDeviceBackend</i> <i>method</i> ), 188	<code>get_pixel_size()</code> ( <i>py-</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 524
<code>get_pending()</code> ( <i>pylablib.core.devio.hid.HIDDevice</i> <i>method</i> ), 195	<code>get_pixel_size()</code> ( <i>py-</i> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 773
<code>get_pending()</code> ( <i>pylablib.core.devio.hid.HIDDevice.Reader</i> <i>method</i> ), 195	<code>get_pixel_size()</code> ( <i>py-</i> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 828
<code>get_phase()</code> ( <i>pylablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 457	<code>get_pixel_width()</code> ( <i>py-</i> <i>lablib.devices.Andor.Shamrock.ShamrockSpectrograph</i> <i>method</i> ), 548
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 470	<code>get_points_number()</code> ( <i>py-</i> <i>lablib.devices.Tektronix.base.DPO2000</i> <i>method</i> ), 897
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 464	<code>get_points_number()</code> ( <i>py-</i> <i>lablib.devices.Tektronix.base.ITektronixScope</i> <i>method</i> ), 884
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 482	<code>get_points_number()</code> ( <i>py-</i> <i>lablib.devices.Tektronix.base.TDS2000</i> <i>method</i> ), 890
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 476	<code>get_polctl_parameters()</code> ( <i>py-</i> <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> <i>method</i> ), 932
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 501	<code>get_port_index()</code> ( <i>in module py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus</i> ), 780
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 488	<code>get_position()</code> ( <i>pylablib.devices.Arcus.performax.Performax2EXStage</i> <i>method</i> ), 558
<code>get_phase()</code> ( <i>pylablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 495	<code>get_position()</code> ( <i>pylablib.devices.Arcus.performax.Performax4EXStage</i> <i>method</i> ), 553
<code>get_pid_parameters()</code> ( <i>py-</i> <i>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</i> <i>method</i> ), 942	
<code>get_piezoet_ctl_status()</code> ( <i>py-</i> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method</i> ), 858	
<code>get_piezoet_drive_params()</code> ( <i>py-</i> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method</i> ), 859	
<code>get_piezoet_feedback_params()</code> ( <i>py-</i> <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> <i>method</i> ), 859	
<code>get_piezoet_feedforward_params()</code> ( <i>py-</i>	



`get_pulse_width()` (pylablib.devices.AWG.generic.GenericAWG method), 457  
`get_pulse_width()` (pylablib.devices.AWG.specific.Agilent33220A method), 470  
`get_pulse_width()` (pylablib.devices.AWG.specific.Agilent33500 method), 464  
`get_pulse_width()` (pylablib.devices.AWG.specific.InstekAFG2000 method), 482  
`get_pulse_width()` (pylablib.devices.AWG.specific.InstekAFG2225 method), 476  
`get_pulse_width()` (pylablib.devices.AWG.specific.RigolDG1000 method), 501  
`get_pulse_width()` (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 488  
`get_pulse_width()` (pylablib.devices.AWG.specific.TektronixAFG1000 method), 492  
`get_python_folder()` (in module pylablib.core.utils.module), 438  
`get_ramp_symmetry()` (pylablib.devices.AWG.generic.GenericAWG method), 457  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.Agilent33220A method), 470  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.Agilent33500 method), 464  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.InstekAFG2000 method), 482  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.InstekAFG2225 method), 476  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.RigolDG1000 method), 501  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 488  
`get_ramp_symmetry()` (pylablib.devices.AWG.specific.TektronixAFG1000 method), 495  
`get_random_track_mode_parameters()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 529  
`get_range()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute method), 536  
`get_range()` (pylablib.devices.Ophir.base.VegaPowerMeter method), 752  
`get_range()` (pylablib.devices.Thorlabs.misc.GenericPM method), 946  
`get_range()` (pylablib.devices.Thorlabs.misc.PM160 method), 951  
`get_range()` (pylablib.devices.Voltcraft.multimeter.VC7055 method), 981  
`get_range_idx()` (pylablib.devices.Ophir.base.VegaPowerMeter method), 752  
`get_range_indices()` (in module pylablib.core.dataproc.utils), 164  
`get_range_info()` (pylablib.devices.Ophir.base.VegaPowerMeter method), 752  
`get_range_limit()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`get_read_mode()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 528  
`get_read_mode()` (pylablib.devices.HighFinesse.wlm.WLM method), 626  
`get_reading()` (pylablib.devices.Keithley.multimeter.Keithley2110 method), 668  
`get_reading()` (pylablib.devices.Thorlabs.misc.GenericPM method), 947  
`get_reading()` (pylablib.devices.Thorlabs.misc.PM160 method), 951  
`get_reading()` (pylablib.devices.Voltcraft.multimeter.VC7055 method), 981  
`get_reading()` (pylablib.devices.Voltcraft.multimeter.VC880 method), 985  
`get_readings()` (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943  
`get_readout_mode()` (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 773  
`get_readout_speed()` (pylablib.devices.DCAM.DCAM.DCAMCamera method), 616  
`get_readout_time()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 528  
`get_readout_time()` (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 774  
`get_real_part_ft()` (in module pylablib.core.dataproc.fourier), 147  
`get_refcell_position()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 536



- method*), 860
- `get_refcell_waveform()` (py-lablib.devices.Sirah.Matisse.SirahMatisse *method*), 857
- `get_refcell_waveform_params()` (py-lablib.devices.Sirah.Matisse.SirahMatisse *method*), 860
- `get_reference_cavity_lock_status()` (py-lablib.devices.M2.solstis.Solstis *method*), 703
- `get_reg()` (pylablib.devices.Lumel.base.LumelRE72Control *method*), 692
- `get_reg()` (pylablib.devices.Omron.base.OmronE5xCControl *method*), 747
- `get_region()` (in module py-lablib.core.dataproc.image), 148
- `get_region_sum()` (in module py-lablib.core.dataproc.image), 148
- `get_register()` (pylablib.devices.NKT.interbus.GenericInterbusM4 *method*), 729
- `get_register()` (pylablib.devices.NKT.interbus.IInterbusM4 *method*), 727
- `get_register()` (pylablib.devices.NKT.interbus.SuperKEx *method*), 730
- `get_register()` (pylablib.devices.NKT.interbus.SuperKFr *method*), 731
- `get_register()` (pylablib.devices.NKT.interbus.SuperKSeg *method*), 732
- `get_register()` (pylablib.devices.NKT.interbus.SuperKSeg *method*), 733
- `get_relative_position()` (in module py-lablib.core.gui.utils), 310
- `get_relative_rectangle()` (in module py-lablib.core.gui.utils), 310
- `get_relay()` (pylablib.devices.Conrad.base.RelayBoard *method*), 598
- `get_relay_setpoints()` (py-lablib.devices.KJL.base.KJL300 *method*), 664
- `get_reload_order()` (in module py-lablib.core.utils.module), 438
- `get_remote_hostname()` (in module py-lablib.core.utils.net), 441
- `get_resistance()` (py-lablib.devices.Lakeshore.base.Lakeshore370 *method*), 678
- `get_roi()` (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera *method*), 517
- `get_roi()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera *method*), 508
- `get_roi()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 529
- `get_roi()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera *method*), 540
- `get_roi()` (pylablib.devices.Basler.pylon.BaslerPylonCamera *method*), 579
- `get_roi()` (pylablib.devices.BitFlow.BitFlow.BitFlowCamera *method*), 593
- `get_roi()` (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber *method*), 586
- `get_roi()` (pylablib.devices.DCAM.DCAM.DCAMCamera *method*), 617
- `get_roi()` (pylablib.devices.IMAQ.IMAQ.IMAQCamera *method*), 644
- `get_roi()` (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber *method*), 635
- `get_roi()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera *method*), 659
- `get_roi()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera *method*), 652
- `get_roi()` (pylablib.devices.interface.camera.IBinROICamera *method*), 1015
- `get_roi()` (pylablib.devices.interface.camera.IROICamera *method*), 1010
- `get_roi()` (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera *method*), 709
- `get_roi()` (pylablib.devices.PCO.SC2.PCOSC2Camera *method*), 758
- `get_roi()` (pylablib.devices.Photometrics.pvcam.PvcamCamera *method*), 774
- `get_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera *method*), 783
- `get_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlow *method*), 809
- `get_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQ *method*), 792
- `get_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoC *method*), 801
- `get_roi()` (pylablib.devices.PrincetonInstruments.picam.PicamCamera *method*), 829
- `get_roi()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera *method*), 851
- `get_roi()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameC *method*), 842
- `get_roi()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera *method*), 907
- `get_roi()` (pylablib.devices.uc480.uc480.UC480Camera *method*), 1027
- `get_roi_limits()` (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera *method*), 517
- `get_roi_limits()` (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera *method*), 508
- `get_roi_limits()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 529
- `get_roi_limits()` (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera *method*), 540

	<i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> method), 540		<i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> method), 829
<code>get_roi_limits()</code>	(py- <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> method), 579	<code>get_roi_limits()</code>	(py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 851
<code>get_roi_limits()</code>	(py- <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 593	<code>get_roi_limits()</code>	(py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842
<code>get_roi_limits()</code>	(py- <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586	<code>get_roi_limits()</code>	(py- <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> method), 907
<code>get_roi_limits()</code>	(py- <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> method), 617	<code>get_roi_limits()</code>	(py- <i>lablib.devices.uc480.uc480.UC480Camera</i> method), 1028
<code>get_roi_limits()</code>	(py- <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 644	<code>get_roi_parameters()</code>	(in module py- <i>lablib.devices.Photometrics.pvcam</i> ), 779
<code>get_roi_limits()</code>	(py- <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635	<code>get_scale()</code>	( <i>pylablib.devices.Thorlabs.elliptec.ElliptecMotor</i> method), 914
<code>get_roi_limits()</code>	(py- <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> method), 659	<code>get_scale()</code>	( <i>pylablib.devices.Thorlabs.kinesis.KinesisMotor</i> method), 928
<code>get_roi_limits()</code>	(py- <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> method), 652	<code>get_scale_units()</code>	(py- <i>lablib.devices.Thorlabs.kinesis.KinesisMotor</i> method), 928
<code>get_roi_limits()</code>	(py- <i>lablib.devices.interface.camera.IBinROICamera</i> method), 1015	<code>get_scan_move_parameters()</code>	(py- <i>lablib.devices.SmarAct.MCS2.MCS2</i> method), 871
<code>get_roi_limits()</code>	(py- <i>lablib.devices.interface.camera.IROICamera</i> method), 1010	<code>get_scan_params()</code>	(py- <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> method), 860
<code>get_roi_limits()</code>	(py- <i>lablib.devices.interface.camera.IROICamera</i> method), 1010	<code>get_scan_position()</code>	(py- <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> method), 860
<code>get_roi_limits()</code>	(py- <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> method), 709	<code>get_scan_position()</code>	(py- <i>lablib.devices.SmarAct.MCS2.MCS2</i> method), 871
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> method), 758	<code>get_scan_status()</code>	(py- <i>lablib.devices.Sirah.Matisse.SirahMatisse</i> method), 860
<code>get_roi_limits()</code>	(py- <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> method), 774	<code>get_screenshot()</code>	(in module <i>pylablib.core.gui.utils</i> ), 310
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusSDK</i> method), 783	<code>get_SDK_version()</code>	(in module py- <i>lablib.devices.Andor.AndorSDK2</i> ), 523
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowGrabber</i> method), 809	<code>get_SDK_version()</code>	(in module py- <i>lablib.devices.SmarAct.MCS2</i> ), 868
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQdxCamera</i> method), 792	<code>get_selected_channel()</code>	(py- <i>lablib.devices.Tektronix.base.DPO2000</i> method), 897
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQdxCamera</i> method), 792	<code>get_selected_channel()</code>	(py- <i>lablib.devices.Tektronix.base.ITektronixScope</i> method), 883
<code>get_roi_limits()</code>	(py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 801	<code>get_selected_channel()</code>	(py- <i>lablib.devices.Tektronix.base.TDS2000</i> method), 890
<code>get_roi_limits()</code>	(py-	<code>get_sensor_curve_index()</code>	(py-

<i>pylablib.devices.Lakeshore.base.Lakeshore218</i> <i>method</i> ), 673	<i>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> <i>method</i> ), 792
<i>get_sensor_info()</i> ( <i>pylablib.devices.Thorlabs.misc.GenericPMT</i> <i>method</i> ), 946	<i>get_setpointf()</i> ( <i>pylablib.devices.Lumel.base.LumelRE72Controller</i> <i>method</i> ), 692
<i>get_sensor_info()</i> ( <i>pylablib.devices.Thorlabs.misc.PM160</i> <i>method</i> ), 951	<i>get_setpointi()</i> ( <i>pylablib.devices.Lumel.base.LumelRE72Controller</i> <i>method</i> ), 693
<i>get_sensor_info()</i> ( <i>pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 904	<i>get_setpointi()</i> ( <i>pylablib.devices.Omron.base.OmronE5xCCController</i> <i>method</i> ), 747
<i>get_sensor_kind()</i> ( <i>pylablib.devices.Cryocon.base.Cryocon1x</i> <i>method</i> ), 600	<i>get_settings()</i> ( <i>pylablib.core.devio.comm_backend.ICommBackendWrapper</i> <i>method</i> ), 192
<i>get_sensor_mode()</i> ( <i>pylablib.devices.Thorlabs.misc.GenericPMT</i> <i>method</i> ), 946	<i>get_settings()</i> ( <i>pylablib.core.devio.interface.IDevice</i> <i>method</i> ), 196
<i>get_sensor_mode()</i> ( <i>pylablib.devices.Thorlabs.misc.PM160</i> <i>method</i> ), 951	<i>get_settings()</i> ( <i>pylablib.core.devio.SCPIDevice</i> <i>method</i> ), 168
<i>get_sensor_mode()</i> ( <i>pylablib.devices.Thorlabs.serial.FW</i> <i>method</i> ), 958	<i>get_settings()</i> ( <i>pylablib.devices.Agilent.pressure.XGS600</i> <i>method</i> ), 506
<i>get_sensor_power()</i> ( <i>pylablib.devices.Lakeshore.base.Lakeshore370</i> <i>method</i> ), 678	<i>get_settings()</i> ( <i>pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 517
<i>get_sensor_reading()</i> ( <i>pylablib.devices.Cryocon.base.Cryocon1x</i> <i>method</i> ), 600	<i>get_settings()</i> ( <i>pylablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 511
<i>get_sensor_reading()</i> ( <i>pylablib.devices.Lakeshore.base.Lakeshore218</i> <i>method</i> ), 673	<i>get_settings()</i> ( <i>pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 531
<i>get_sensor_type()</i> ( <i>pylablib.devices.Lakeshore.base.Lakeshore218</i> <i>method</i> ), 672	<i>get_settings()</i> ( <i>pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 542
<i>get_sensor_voltage()</i> ( <i>pylablib.devices.Attocube.anc350.ANC350</i> <i>method</i> ), 571	<i>get_settings()</i> ( <i>pylablib.devices.Andor.Shamrock.ShamrockSpectrograph</i> <i>method</i> ), 549
<i>get_serial_parameter()</i> ( <i>pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 517	<i>get_settings()</i> ( <i>pylablib.devices.Arcus.performax.GenericPerformaxStage</i> <i>method</i> ), 552
<i>get_serial_parameter()</i> ( <i>pylablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 508	<i>get_settings()</i> ( <i>pylablib.devices.Arcus.performax.Performax2EXStage</i> <i>method</i> ), 558
<i>get_serial_params()</i> ( <i>pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 517	<i>get_settings()</i> ( <i>pylablib.devices.Arcus.performax.Performax4EXStage</i> <i>method</i> ), 556
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 644	<i>get_settings()</i> ( <i>pylablib.devices.Arcus.performax.PerformaxDMXJSAS</i> <i>method</i> ), 562
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.Arduino.base.IArduinoDevice</i> <i>method</i> ), 565
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.Attocube.anc300.ANC300</i> <i>method</i> ), 569
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.Attocube.anc350.ANC350</i> <i>method</i> ), 573
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 459
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 470
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 464
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 482
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 476
<i>get_serial_params()</i> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 636	<i>get_settings()</i> ( <i>pylablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 476

method), 501  
get\_settings() (pylablib.devices.AWG.specific.RSInstekAgilent21000 method), 489  
get\_settings() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 495  
get\_settings() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 582  
get\_settings() (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 593  
get\_settings() (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGraber method), 589  
get\_settings() (pylablib.devices.Conrad.base.RelayBoard method), 599  
get\_settings() (pylablib.devices.Cryocon.base.CryoconCamera method), 601  
get\_settings() (pylablib.devices.Cryomagnetics.base.LM600 method), 606  
get\_settings() (pylablib.devices.Cryomagnetics.base.LM610 method), 610  
get\_settings() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 619  
get\_settings() (pylablib.devices.ElektroAutomatik.base.BS1000 method), 625  
get\_settings() (pylablib.devices.HighFinesse.wlm.WLM method), 629  
get\_settings() (pylablib.devices.Hubner.Cobolt.Cobolt method), 632  
get\_settings() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 644  
get\_settings() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGraber method), 639  
get\_settings() (pylablib.devices.IMAQdx.IMAQdx.Ethernet method), 659  
get\_settings() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 654  
get\_settings() (pylablib.devices.interface.camera.IAttribute method), 998  
get\_settings() (pylablib.devices.interface.camera.IBinRange method), 1017  
get\_settings() (pylablib.devices.interface.camera.ICamera method), 993  
get\_settings() (pylablib.devices.interface.camera.IExposure method), 1007  
get\_settings() (pylablib.devices.interface.camera.IGrabber method), 1003  
get\_settings() (pylablib.devices.interface.camera.IROI method), 1012  
get\_settings() (pylablib.devices.interface.stage.IMultiAxisStage method), 1022  
get\_settings() (pylablib.devices.interface.stage.IStage method), 1021  
get\_settings() (pylablib.devices.Keithley.multimeter.Keithley2500 method), 669  
get\_settings() (pylablib.devices.KJL.base.KJL300 method), 664  
get\_settings() (pylablib.devices.Lakeshore.base.Lakeshore218 method), 675  
get\_settings() (pylablib.devices.Lakeshore.base.Lakeshore370 method), 680  
get\_settings() (pylablib.devices.LaserQuantum.base.Finesse method), 684  
get\_settings() (pylablib.devices.Leybold.base.GenericITR method), 687  
get\_settings() (pylablib.devices.Leybold.base.ITR90 method), 688  
get\_settings() (pylablib.devices.LighthousePhotonics.base.SproutG method), 691  
get\_settings() (pylablib.devices.Lumel.base.LumelRE72Controller method), 693  
get\_settings() (pylablib.devices.M2.base.ICEBlocDevice method), 697  
get\_settings() (pylablib.devices.M2.emm.EMM method), 700  
get\_settings() (pylablib.devices.M2.solstis.Solstis method), 706  
get\_settings() (pylablib.devices.Mightex.MightexSSeries.MightexSSeries method), 712  
get\_settings() (pylablib.devices.Modbus.modbus.GenericModbusRTU method), 716  
get\_settings() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 739  
get\_settings() (pylablib.devices.NI.daq.NIDAQ method), 724  
get\_settings() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 727  
get\_settings() (pylablib.devices.NKT.interbus.GenericInterbusModule method), 729  
get\_settings() (pylablib.devices.NKT.interbus.IInterbusModule method), 728  
get\_settings() (pylablib.devices.NKT.interbus.InterbusSystem method), 734  
get\_settings() (pylablib.devices.NKT.interbus.SuperKExtremeInterbusModule method), 730  
get\_settings() (pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule method), 731  
get\_settings() (pylablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule method), 732  
get\_settings() (pylablib.devices.NKT.interbus.SuperKSelectInterbusModule method), 733  
get\_settings() (pylablib.devices.Omron.base.OmronE5xCCController method), 747  
get\_settings() (pylablib.devices.Ophir.base.OphirDevice method), 750  
get\_settings() (pylablib.devices.Ophir.base.VegaPowerMeter method), 753  
get\_settings() (pylablib.devices.OZOptics.base.DD100 method), 744  
get\_settings() (pylablib.devices.OZOptics.base.EPC04 method), 744



method), 746

get\_settings() (pylablib.devices.OZOptics.base.OZOpticsDevice method), 741

get\_settings() (pylablib.devices.OZOptics.base.TF100 method), 742

get\_settings() (pylablib.devices.PCO.SC2.PCOSC2Camera method), 761

get\_settings() (pylablib.devices.Pfeiffer.base.DPG202 method), 768

get\_settings() (pylablib.devices.Pfeiffer.base.TPG260 method), 766

get\_settings() (pylablib.devices.Photometrics.pvcam.Pvcam method), 777

get\_settings() (pylablib.devices.PhotonFocus.PhotonFocus method), 785

get\_settings() (pylablib.devices.PhotonFocus.PhotonFocus method), 809

get\_settings() (pylablib.devices.PhotonFocus.PhotonFocus method), 792

get\_settings() (pylablib.devices.PhotonFocus.PhotonFocus method), 801

get\_settings() (pylablib.devices.PhysikInstrumente.base.PI method), 815

get\_settings() (pylablib.devices.PhysikInstrumente.base.PI method), 821

get\_settings() (pylablib.devices.PhysikInstrumente.base.PI method), 818

get\_settings() (pylablib.devices.PrincetonInstruments.pigeon.Pigeon method), 831

get\_settings() (pylablib.devices.Rigol.power\_supply.DP416 method), 836

get\_settings() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware method), 851

get\_settings() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware method), 846

get\_settings() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 861

get\_settings() (pylablib.devices.SmarAct.MCS2.MCS2 method), 872

get\_settings() (pylablib.devices.SmarAct.scu3d.SC3D method), 875

get\_settings() (pylablib.devices.Standa.base.Standa8SM method), 880

get\_settings() (pylablib.devices.Tektronix.base.DPO2000 method), 897

get\_settings() (pylablib.devices.Tektronix.base.ITektronix method), 886

get\_settings() (pylablib.devices.Tektronix.base.TDS2000 method), 890

get\_settings() (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 915

get\_settings() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 918

get\_settings() (pylablib.devices.Thorlabs.kinesis.Kinesis method), 922

get\_settings() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 933

get\_settings() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 940

get\_settings() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 937

get\_settings() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 944

get\_settings() (pylablib.devices.Thorlabs.kinesis.MFF method), 926

get\_settings() (pylablib.devices.Thorlabs.misc.GenericPM method), 948

get\_settings() (pylablib.devices.Thorlabs.misc.PM160 method), 951

get\_settings() (pylablib.devices.Thorlabs.misc.BitFlowCamera method), 959

get\_settings() (pylablib.devices.Thorlabs.serial.FW method), 959

get\_settings() (pylablib.devices.Thorlabs.serial.FWv1 method), 962

get\_settings() (pylablib.devices.Thorlabs.serial.MDT69xA method), 965

get\_settings() (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955

get\_settings() (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 909

get\_settings() (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 970

get\_settings() (pylablib.devices.Trinamic.base.TMCM1110 method), 975

get\_settings() (pylablib.devices.Trinamic.base.TMCMx110 method), 977

get\_settings() (pylablib.devices.uc480.uc480.UC480Camera method), 1029

get\_settings() (pylablib.devices.Voltcraft.multimeter.VC7055 method), 982

get\_settings() (pylablib.devices.Voltcraft.multimeter.VC880 method), 986

get\_settings() (pylablib.devices.Windows.joystick.Joystick method), 988

get\_shape() (in module pylablib.core.utils.array\_utils), 371

get\_shutter() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526

get\_shutter() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 538

get\_shutter() (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547

get\_shutter\_parameters() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526

get\_shutter\_status() (pylablib.devices.LaserQuantum.base.Finesse method), 683

get\_shutter\_status() (pylablib.devices.LaserQuantum.base.Finesse method), 683

`pylablib.devices.LighthousePhotonics.base.SproutG.get_state()` (`pylablib.devices.Thorlabs.kinesis.MFF`  
`method`), 690 `method`), 925  
`get_single_track_mode_parameters()` (`py-` `get_stats()` (in module `pylablib.core.thread.profile`),  
`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` 366  
`method`), 529 `get_status()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`method`), 524  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.B`  
`pylablib.core.gui.value_handling.CheckboxValueHandler` `method`), 539  
`method`), 320 `method`), 539  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.Arcus.performax.Performax2EXStage`  
`pylablib.core.gui.value_handling.ComboBoxValueHandler` `method`), 558  
`method`), 323 `get_status()` (`pylablib.devices.Arcus.performax.Performax4EXStage`  
`method`), 554  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.Arcus.performax.PerformaxDMXJSStage`  
`pylablib.core.gui.value_handling.IBoolValueHandler` `method`), 561  
`method`), 319 `method`), 561  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.Attocube.anc350.ANC350`  
`pylablib.core.gui.value_handling.ISingleValueHandler` `method`), 571  
`method`), 316 `get_status()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera.Schedul`  
`method`), 318 `method`), 580  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera.BufferM`  
`pylablib.core.gui.value_handling.LabelValueHandler` `method`), 591  
`method`), 317 `method`), 591  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.B`  
`pylablib.core.gui.value_handling.LineEditValueHandler` `method`), 587  
`method`), 317 `get_status()` (`pylablib.devices.DCAM.DCAM.DCAMCamera`  
`method`), 617  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.ElektroAutomatik.base.PS2000B`  
`pylablib.core.gui.value_handling.ProgressBarValueHandler` `method`), 624  
`method`), 324 `method`), 624  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesC`  
`pylablib.core.gui.value_handling.PushButtonValueHandler` `method`), 710  
`method`), 321 `get_status()` (`pylablib.devices.NKT.interbus.GenericInterbusModule`  
`method`), 729  
`get_single_value()` (`py-` `get_status()` (`pylablib.devices.NKT.interbus.IInterbusModule`  
`pylablib.core.gui.value_handling.ToolButtonValueHandler` `method`), 727  
`method`), 322 `method`), 727  
`get_slit_width()` (`py-` `get_status()` (`pylablib.devices.NKT.interbus.SuperKExtremeInterbusMo`  
`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` `method`), 730  
`method`), 546 `get_status()` (`pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusM`  
`method`), 731  
`get_slowpiezo_ctl_params()` (`py-` `get_status()` (`pylablib.devices.NKT.interbus.SuperKSelectDriverInterbus`  
`pylablib.devices.Sirah.Matisse.SirahMatisse` `method`), 732  
`method`), 859 `method`), 732  
`get_slowpiezo_ctl_status()` (`py-` `get_status()` (`pylablib.devices.NKT.interbus.SuperKSelectInterbusModu`  
`pylablib.devices.Sirah.Matisse.SirahMatisse` `method`), 733  
`method`), 859 `get_status()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusB`  
`method`), 806  
`get_slowpiezo_position()` (`py-` `get_status()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusS`  
`pylablib.devices.Sirah.Matisse.SirahMatisse` `method`), 797  
`method`), 859 `method`), 797  
`get_software_version()` (`py-` `get_status()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCam`  
`pylablib.devices.Pfeiffer.base.DPG202` `method`), 848  
`method`), 768 `get_status()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFra`  
`method`), 843  
`get_spectrographs_number()` (in module `py-` `get_status()` (`pylablib.devices.SmarAct.MCS2.MCS2`  
`pylablib.devices.Andor.Shamrock`), 544 `method`), 870  
`get_speed_mode()` (`py-` `get_status()` (`pylablib.devices.SmarAct.scu3d.SCU3D`  
`pylablib.devices.Thorlabs.serial.FW` `method`), 875  
`method`), 958 `method`), 875  
`get_stage()` (`pylablib.devices.Thorlabs.kinesis.KinesisMoget` `get_status()` (`pylablib.devices.Standa.base.Standa8SMC`  
`method`), 928 `method`), 878

`get_status()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913  
`get_status()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 929  
`get_status()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 939  
`get_status()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935  
`get_status()` (pylablib.devices.Thorlabs.kinesis.MFF method), 924  
`get_status()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 905  
`get_status_line()` (in module py-lablib.devices.PCO.SC2), 763  
`get_status_line_mode()` (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 759  
`get_status_line_position()` (in module py-lablib.devices.PhotonFocus.PhotonFocus), 813  
`get_status_line_roi()` (in module py-lablib.devices.interface.camera), 1020  
`get_status_lines()` (in module py-lablib.devices.AlliedVision.Bonito), 522  
`get_status_lines()` (in module py-lablib.devices.PCO.SC2), 763  
`get_status_lines()` (in module py-lablib.devices.PhotonFocus.PhotonFocus), 812  
`get_status_n()` (pylablib.devices.Arcus.performax.Performax2EXStage method), 558  
`get_status_n()` (pylablib.devices.Arcus.performax.Performax450Stage method), 554  
`get_status_n()` (pylablib.devices.Arcus.performax.PerformaxDMXStage method), 561  
`get_status_n()` (pylablib.devices.Attocube.anc350.ANC350 method), 571  
`get_status_n()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 870  
`get_status_n()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 928  
`get_status_n()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 938  
`get_status_n()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935  
`get_status_n()` (pylablib.devices.Thorlabs.kinesis.MFF method), 924  
`get_step_move_parameters()` (py-lablib.devices.SmarAct.MCS2.MCS2 method), 870  
`get_stepper_motor_calibration()` (py-lablib.devices.Standa.base.Standa8SMC method), 878  
`get_string_filter()` (in module py-

lablib.core.utils.string), 450  
`get_sublayout()` (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 243  
`get_sublayout()` (py-lablib.core.gui.widgets.container.QDialogContainer method), 257  
`get_sublayout()` (py-lablib.core.gui.widgets.container.QFrameContainer method), 253  
`get_sublayout()` (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 262  
`get_sublayout()` (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 267  
`get_sublayout()` (py-lablib.core.gui.widgets.container.QWidgetContainer method), 248  
`get_sublayout()` (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 280  
`get_sublayout()` (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 283  
`get_sublayout()` (py-lablib.core.gui.widgets.param\_table.ParamTable method), 294  
`get_sublayout()` (py-lablib.core.gui.widgets.param\_table.StatusTable method), 304  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 244  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.QDialogContainer method), 257  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.QFrameContainer method), 253  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 262  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 267  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.container.QWidgetContainer method), 248  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 281  
`get_sublayout_kind()` (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget

<i>method</i> ), 283		701	
<code>get_sublayout_kind()</code>	(py-lablib.core.gui.widgets.param_table.ParamTable <i>method</i> ), 294	<code>get_table_line()</code>	(py-lablib.core.fileio.savefile.CSVTableOutputFileFormat <i>method</i> ), 225
<code>get_sublayout_kind()</code>	(py-lablib.core.gui.widgets.param_table.StatusTable <i>method</i> ), 304	<code>get_target_position()</code>	(py-lablib.devices.Attocube.anc350.ANC350 <i>method</i> ), 571
<code>get_subsampling()</code>	(py-lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1027	<code>get_target_position()</code>	(py-lablib.devices.PhysikInstrumente.base.PIE515 <i>method</i> ), 820
<code>get_supported_baudrates()</code>	(py-lablib.devices.Ophir.base.VegaPowerMeter <i>method</i> ), 753	<code>get_target_position()</code>	(py-lablib.devices.PhysikInstrumente.base.PIE516 <i>method</i> ), 817
<code>get_supported_binning_modes()</code>	(py-lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 775	<code>get_target_position()</code>	(py-lablib.devices.SmarAct.MCS2.MCS2 <i>method</i> ), 871
<code>get_supported_binning_modes()</code>	(py-lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1027	<code>get_temperature()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 524
<code>get_supported_sensor_modes()</code>	(py-lablib.devices.Thorlabs.misc.GenericPM <i>method</i> ), 946	<code>get_temperature()</code>	(py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 538
<code>get_supported_sensor_modes()</code>	(py-lablib.devices.Thorlabs.misc.PM160 <i>method</i> ), 952	<code>get_temperature()</code>	(py-lablib.devices.Cryocon.base.Cryocon1x <i>method</i> ), 600
<code>get_supported_subsampling_modes()</code>	(py-lablib.devices.uc480.uc480.UC480Camera <i>method</i> ), 1027	<code>get_temperature()</code>	(py-lablib.devices.Lakeshore.base.Lakeshore218 <i>method</i> ), 673
<code>get_switch_polarity()</code>	(py-lablib.devices.Trinamic.base.TMCM1110 <i>method</i> ), 974	<code>get_temperature()</code>	(py-lablib.devices.Lakeshore.base.Lakeshore370 <i>method</i> ), 678
<code>get_switch_polarity()</code>	(py-lablib.devices.Trinamic.base.TMCMx110 <i>method</i> ), 978	<code>get_temperature()</code>	(py-lablib.devices.PCO.SC2.PCOS2Camera <i>method</i> ), 756
<code>get_switch_settings()</code>	(py-lablib.devices.Pfeiffer.base.TPG260 <i>method</i> ), 765	<code>get_temperature()</code>	(py-lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 773
<code>get_switch_status()</code>	(py-lablib.devices.Pfeiffer.base.TPG260 <i>method</i> ), 766	<code>get_temperature_range()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 525
<code>get_switcher_mode()</code>	(py-lablib.devices.HighFinesse.wlm.WLM <i>method</i> ), 627	<code>get_temperature_setpoint()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 524
<code>get_system_info()</code>	(py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera <i>method</i> ), 801	<code>get_temperature_setpoint()</code>	(py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 538
<code>get_system_info()</code>	(py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 851	<code>get_temperature_setpoint()</code>	(py-lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 773
<code>get_system_info()</code>	(py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber <i>method</i> ), 842	<code>get_temperature_status()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 524
<code>get_system_status()</code>	(py-lablib.devices.M2.solstis.Solstis <i>method</i> ),	<code>get_temperatures()</code>	(py-lablib.devices.LaserQuantum.base.Finesse



method), 683

get\_temperatures() (py-lablib.devices.Toptica.ibeam.TopicalBeam method), 970

get\_terascan\_status() (py-lablib.devices.M2.emm.EMM method), 699

get\_terascan\_status() (py-lablib.devices.M2.solstis.Solstis method), 704

get\_thinet\_ctl\_params() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858

get\_thinet\_ctl\_status() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858

get\_thinet\_error\_signal() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858

get\_thinet\_power() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 857

get\_timeout() (pylablib.core.devio.comm\_backend.FT232DeviceBackend method), 179

get\_timeout() (pylablib.core.devio.comm\_backend.HIDDeviceBackend method), 187

get\_timeout() (pylablib.core.devio.comm\_backend.IDeviceBackend method), 171

get\_timeout() (pylablib.core.devio.comm\_backend.NetworkDeviceBackend method), 182

get\_timeout() (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 184

get\_timeout() (pylablib.core.devio.comm\_backend.RecorderDeviceBackend method), 190

get\_timeout() (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 176

get\_timeout() (pylablib.core.devio.comm\_backend.VisaDeviceBackend method), 174

get\_timeout() (pylablib.core.devio.hid.HIDDevice method), 195

get\_timeout() (pylablib.core.utils.net.ClientSocket method), 442

get\_timestamp\_clock\_frequency() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 906

get\_top\_parent() (in module pylablib.core.gui.utils), 309

get\_transfer\_info() (py-lablib.devices.DCAM.DCAM.DCAMCamera method), 618

get\_trigger\_input() (py-lablib.devices.Attocube.anc300.ANC300 method), 568

get\_trigger\_interleave() (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 783

get\_trigger\_interleave() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 809

get\_trigger\_interleave() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 792

get\_trigger\_interleave() (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 801

get\_trigger\_level() (py-lablib.devices.Tektronix.base.DPO2000 method), 897

get\_trigger\_level() (py-lablib.devices.Tektronix.base.ITektronixScope method), 882

get\_trigger\_level() (py-lablib.devices.Tektronix.base.TDS2000 method), 890

get\_trigger\_level\_limits() (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 527

get\_trigger\_mode() (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 527

get\_trigger\_mode() (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 538

get\_trigger\_mode() (py-lablib.devices.DCAM.DCAM.DCAMCamera method), 616

get\_trigger\_mode() (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 756

get\_trigger\_mode() (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 774

get\_trigger\_mode() (py-lablib.devices.Tektronix.base.DPO2000 method), 897

get\_trigger\_mode() (py-lablib.devices.Tektronix.base.ITektronixScope method), 882

get\_trigger\_mode() (py-lablib.devices.Tektronix.base.TDS2000 method), 890

get\_trigger\_mode() (py-lablib.devices.Thorlabs.serial.FW method), 958

get\_trigger\_mode() (py-lablib.devices.Thorlabs.serial.FWv1 method), 961

get\_trigger\_mode() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 906

- method*), 905
- `get_trigger_mode()` (py-lablib.devices.uc480.uc480.UC480Camera *method*), 1025
- `get_trigger_slope()` (py-lablib.devices.AWG.generic.GenericAWG *method*), 458
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.Agilent33220A *method*), 470
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.Agilent33500 *method*), 464
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.InstekAFG2000 *method*), 482
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.InstekAFG2225 *method*), 476
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.RigolDG1000 *method*), 501
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 489
- `get_trigger_slope()` (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 495
- `get_trigger_source()` (py-lablib.devices.AWG.generic.GenericAWG *method*), 458
- `get_trigger_source()` (py-lablib.devices.AWG.specific.Agilent33220A *method*), 470
- `get_trigger_source()` (py-lablib.devices.AWG.specific.Agilent33500 *method*), 464
- `get_trigger_source()` (py-lablib.devices.AWG.specific.InstekAFG2000 *method*), 482
- `get_trigger_source()` (py-lablib.devices.AWG.specific.InstekAFG2225 *method*), 477
- `get_trigger_source()` (py-lablib.devices.AWG.specific.RigolDG1000 *method*), 501
- `get_trigger_source()` (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 489
- `get_trigger_source()` (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 495
- `get_trigger_state()` (py-lablib.devices.Tektronix.base.DPO2000 *method*), 897
- `get_trigger_state()` (py-lablib.devices.Tektronix.base.ITektronixScope *method*), 882
- `get_trigger_state()` (py-lablib.devices.Tektronix.base.TDS2000 *method*), 890
- `get_turret()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph *method*), 546
- `get_type()` (pylablib.core.dataproc.table\_wrap.Array1DWrapper *method*), 154
- `get_type()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper *method*), 158
- `get_type()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper *method*), 160
- `get_type()` (pylablib.core.dataproc.table\_wrap.I1DWrapper *method*), 153
- `get_type()` (pylablib.core.dataproc.table\_wrap.I2DWrapper *method*), 156
- `get_type()` (pylablib.core.dataproc.table\_wrap.IGenWrapper *method*), 152
- `get_type()` (pylablib.core.dataproc.table\_wrap.Series1DWrapper *method*), 155
- `get_type()` (pylablib.devices.Cryomagnetics.base.LM500 *method*), 604
- `get_type()` (pylablib.devices.Cryomagnetics.base.LM510 *method*), 610
- `get_units()` (pylablib.devices.Agilent.pressure.XGS600 *method*), 506
- `get_units()` (pylablib.devices.Leybold.base.GenericITR *method*), 686
- `get_units()` (pylablib.devices.Leybold.base.ITR90 *method*), 688
- `get_units()` (pylablib.devices.Ophir.base.VegaPowerMeter *method*), 752
- `get_units()` (pylablib.devices.Pfeiffer.base.TPG260 *method*), 764
- `get_update()` (pylablib.devices.Leybold.base.GenericITR *method*), 686
- `get_update()` (pylablib.devices.Leybold.base.ITR90 *method*), 688
- `get_usb_device_info()` (in module py-lablib.devices.Arcus.performax), 551
- `get_usb_devices_number()` (in module py-lablib.devices.Attocube.anc350), 570
- `get_usb_devices_number()` (in module py-lablib.devices.Newport.picomotor), 736
- `get_value()` (in module py-lablib.core.utils.ctypes\_wrap), 372
- `get_value()` (pylablib.core.gui.value\_handling.CheckboxValueHandler *method*), 320
- `get_value()` (pylablib.core.gui.value\_handling.ComboBoxValueHandler *method*), 323
- `get_value()` (pylablib.core.gui.value\_handling.GUIValues

method), 328

get\_value() (pylablib.core.gui.value\_handling.IBoolValueHandler method), 319

get\_value() (pylablib.core.gui.value\_handling.IIndicatorHandler method), 325

get\_value() (pylablib.core.gui.value\_handling.ISingleValueHandler method), 316

get\_value() (pylablib.core.gui.value\_handling.IValueHandler method), 311

get\_value() (pylablib.core.gui.value\_handling.LabelIndicatorHandler method), 326

get\_value() (pylablib.core.gui.value\_handling.LabelValueHandler method), 318

get\_value() (pylablib.core.gui.value\_handling.LineEditValueHandler method), 317

get\_value() (pylablib.core.gui.value\_handling.ProgressBoxValueHandler method), 324

get\_value() (pylablib.core.gui.value\_handling.PropertyValueHandler method), 314

get\_value() (pylablib.core.gui.value\_handling.PushButtonValueHandler method), 321

get\_value() (pylablib.core.gui.value\_handling.StandardIntegerValueHandler method), 325

get\_value() (pylablib.core.gui.value\_handling.StandardValueHandler method), 315

get\_value() (pylablib.core.gui.value\_handling.ToolButtonValueHandler method), 322

get\_value() (pylablib.core.gui.value\_handling.VirtualValueHandler method), 313

get\_value() (pylablib.core.gui.widgets.button.ToggleButton method), 232

get\_value() (pylablib.core.gui.widgets.button\_selector.ButtonSelector method), 233

get\_value() (pylablib.core.gui.widgets.combo\_box.ComboBox method), 235

get\_value() (pylablib.core.gui.widgets.container.IQContainer method), 237

get\_value() (pylablib.core.gui.widgets.container.IQWidgetContainer method), 244

get\_value() (pylablib.core.gui.widgets.container.QContainer method), 240

get\_value() (pylablib.core.gui.widgets.container.QDialog method), 257

get\_value() (pylablib.core.gui.widgets.container.QFrameContainer method), 253

get\_value() (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 262

get\_value() (pylablib.core.gui.widgets.container.QScrollArea method), 270

get\_value() (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 267

get\_value() (pylablib.core.gui.widgets.container.QTabContainer method), 273

get\_value() (pylablib.core.gui.widgets.container.QWidgetContainer method), 278

get\_value() (pylablib.core.gui.widgets.edit.NumEdit method), 248

get\_value() (pylablib.core.gui.widgets.edit.TextEdit method), 277

get\_value() (pylablib.core.gui.widgets.label.EnumLabel method), 275

get\_value() (pylablib.core.gui.widgets.label.NumLabel method), 278

get\_value() (pylablib.core.gui.widgets.label.TextLabel method), 279

get\_value() (pylablib.core.gui.widgets.param\_table.ParamTable method), 291

get\_value() (pylablib.core.gui.widgets.param\_table.StatusTable method), 304

get\_value() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330

get\_value() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331

get\_value() (pylablib.core.thread.synchronizing.QThreadNotifier method), 367

get\_value() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute method), 535

get\_value() (pylablib.devices.Attocube.anc350.ANC350 method), 570

get\_value() (pylablib.devices.Basler.pylon.BaslerPylonAttribute method), 577

get\_value() (pylablib.devices.DCAM.DCAM.DCAMAttribute method), 614

get\_value() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute method), 650

get\_value() (pylablib.devices.Pfeiffer.base.DPG202 method), 767

get\_value() (pylablib.devices.Photometrics.pvcam.PvcamAttribute method), 771

get\_value() (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute method), 781

get\_value() (pylablib.devices.PrincetonInstruments.picam.PicamAttribute method), 827

get\_value() (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute method), 840

get\_value\_changed\_signal() (pylablib.core.gui.value\_handling.CheckboxValueHandler method), 320

get\_value\_changed\_signal() (pylablib.core.gui.value\_handling.ComboBoxValueHandler method), 323

get\_value\_changed\_signal() (pylablib.core.gui.value\_handling.GUIValues method), 328

get\_value\_changed\_signal() (pylablib.core.gui.value\_handling.IBoolValueHandler method), 319

get\_value\_changed\_signal() (pylablib.core.gui.value\_handling.IIntegerValueHandler method), 316

<a href="#">lablib.core.gui.value_handling.ISingleValueHandler method</a> ), 317		<a href="#">lablib.core.gui.widgets.container.QTabContainer method</a> ), 273
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.IValueHandler method</a> ), 312	<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QWidgetContainer method</a> ), 248	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.LabelValueHandling method</a> ), 318	<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.param_table.ParamTable method</a> ), 294	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.LineEditValueHandling method</a> ), 317	<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.param_table.StatusTable method</a> ), 304	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.ProgressBarValueHandling method</a> ), 324	<a href="#">get_value_sync()</a> ( <a href="#">py-lablib.core.thread.callsync.QCallResultSynchronizer method</a> ), 330	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.PropertyValueHandling method</a> ), 314	<a href="#">get_value_sync()</a> ( <a href="#">py-lablib.core.thread.callsync.QDirectResultSynchronizer method</a> ), 331	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.PushButtonValueHandling method</a> ), 321	<a href="#">get_value_sync()</a> ( <a href="#">py-lablib.core.thread.synchronizing.QThreadNotifier method</a> ), 367	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.StandardValueHandling method</a> ), 316	<a href="#">get_variable()</a> ( <a href="#">pylablib.core.thread.controller.QTaskThread method</a> ), 358	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.ToolButtonValueHandling method</a> ), 322	<a href="#">get_variable()</a> ( <a href="#">pylablib.core.thread.controller.QThreadController method</a> ), 347	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.value_handling.VirtualValueHandling method</a> ), 313	<a href="#">get_vcr_function_parameters()</a> ( <a href="#">py-lablib.devices.Keithley.multimeter.Keithley2110 method</a> ), 666	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.IQContainer method</a> ), 238	<a href="#">get_velocity()</a> ( <a href="#">pylablib.devices.PhysikInstrumente.base.PIE516 method</a> ), 817	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.IQWidgetContainer method</a> ), 244	<a href="#">get_velocity()</a> ( <a href="#">pylablib.devices.Thorlabs.elliptec.ElliptecMotor method</a> ), 914	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QContainer method</a> ), 240	<a href="#">get_velocity_factor()</a> ( <a href="#">py-lablib.devices.Trinamic.base.TMCM1110 method</a> ), 975	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QDialogContainer method</a> ), 257	<a href="#">get_velocity_factor()</a> ( <a href="#">py-lablib.devices.Trinamic.base.TMCMx110 method</a> ), 978	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QFrameContainer method</a> ), 253	<a href="#">get_velocity_parameters()</a> ( <a href="#">py-lablib.devices.Newport.picomotor.Picomotor8742 method</a> ), 738	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QGroupBoxContainer method</a> ), 262	<a href="#">get_velocity_parameters()</a> ( <a href="#">py-lablib.devices.Thorlabs.kinesis.KinesisMotor method</a> ), 930	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QScrollAreaContainer method</a> ), 270	<a href="#">get_velocity_parameters()</a> ( <a href="#">py-lablib.devices.Trinamic.base.TMCM1110 method</a> ), 974	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QScrollAreaContainer method</a> ), 267	<a href="#">get_velocity_parameters()</a> ( <a href="#">py-lablib.devices.Trinamic.base.TMCMx110 method</a> ), 978	
<a href="#">get_value_changed_signal()</a> ( <a href="#">py-lablib.core.gui.widgets.container.QScrollAreaContainer method</a> ), 267	<a href="#">generate_official_position()</a> ( <a href="#">py-lablib.devices.Tektronix.base.DPO2000 method</a> ), 897	



<code>get_vertical_position()</code>	(py-lablib.devices.Tektronix.base.ITektronixScope method), 883	<code>get_vertical_position()</code>	(py-lablib.devices.Tektronix.base.TDS2000 method), 890
<code>get_vertical_span()</code>	(py-lablib.devices.Tektronix.base.DPO2000 method), 897	<code>get_voltages()</code>	(py-lablib.devices.OZOptics.base.EPC04 method), 744
<code>get_vertical_span()</code>	(py-lablib.devices.Tektronix.base.ITektronixScope method), 883	<code>get_vsspeed()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526
<code>get_vertical_span()</code>	(py-lablib.devices.Tektronix.base.TDS2000 method), 890	<code>get_vsspeed_period()</code>	(py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526
<code>get_voltage()</code>	(pylablib.devices.Attocube.anc300.ANC300 method), 567	<code>get_warning_status()</code>	(py-lablib.devices.LighthousePhotonics.base.SproutG method), 690
<code>get_voltage()</code>	(pylablib.devices.Attocube.anc350.ANC350 method), 572	<code>get_waveform()</code>	(pylablib.devices.OZOptics.base.EPC04 method), 745
<code>get_voltage()</code>	(pylablib.devices.ElektroAutomatik.base.PS2000B method), 624	<code>get_wavelength()</code>	(py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546
<code>get_voltage()</code>	(pylablib.devices.PhysikInstrumente.base.PIE515 method), 820	<code>get_wavelength()</code>	(py-lablib.devices.HighFinesse.wlm.WLM method), 627
<code>get_voltage()</code>	(pylablib.devices.PhysikInstrumente.base.PIE515 method), 816	<code>get_wavelength()</code>	(py-lablib.devices.Ophir.base.VegaPowerMeter method), 752
<code>get_voltage()</code>	(pylablib.devices.PhysikInstrumente.base.PIE515 method), 817	<code>get_wavelength()</code>	(py-lablib.devices.OZOptics.base.TF100 method), 741
<code>get_voltage()</code>	(pylablib.devices.Rigol.power_supply.DP144 method), 834	<code>get_wavelength()</code>	(py-lablib.devices.Thorlabs.misc.GenericPM method), 947
<code>get_voltage()</code>	(pylablib.devices.Thorlabs.serial.MDT69xA method), 964	<code>get_wavelength()</code>	(py-lablib.devices.Thorlabs.misc.PM160 method), 952
<code>get_voltage_input_parameters()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 720	<code>get_wavelength_correction()</code>	(py-lablib.devices.Thorlabs.misc.PM160 method), 952
<code>get_voltage_lower_limit()</code>	(py-lablib.devices.PhysikInstrumente.base.PIE515 method), 820		
<code>get_voltage_lower_limit()</code>	(py-lablib.devices.PhysikInstrumente.base.PIE516 method), 817		
<code>get_voltage_output_buffer_fill()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 722		
<code>get_voltage_output_channels()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 722		
<code>get_voltage_output_clock_parameters()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 723		
<code>get_voltage_output_parameters()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 722		
<code>get_voltage_outputs()</code>	(py-lablib.devices.NI.daq.NIDAQ method), 722		
<code>get_voltage_pattern()</code>	(py-lablib.devices.Attocube.anc300.ANC300 method), 567		
<code>get_voltage_range()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939		
<code>get_voltage_range()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939		

`lablib.devices.OZOptics.base.TF100` method), 741  
`get_wavelength_info()` (py-lablib.devices.Ophir.base.VegaPowerMeter method), 752  
`get_wavelength_limits()` (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546  
`get_wavelength_range()` (py-lablib.devices.Thorlabs.misc.GenericPM method), 947  
`get_wavelength_range()` (py-lablib.devices.Thorlabs.misc.PM160 method), 952  
`get_wfmpre()` (pylablib.devices.Tektronix.base.DPO2000 method), 897  
`get_wfmpre()` (pylablib.devices.Tektronix.base.ITektronixScope method), 884  
`get_wfmpre()` (pylablib.devices.Tektronix.base.TDS2000 method), 890  
`get_white_balance_matrix()` (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 904  
`get_widget()` (pylablib.core.gui.value\_handling.GUIValue method), 327  
`get_widget()` (pylablib.core.gui.widgets.container.IQContainer method), 237  
`get_widget()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 244  
`get_widget()` (pylablib.core.gui.widgets.container.QContainer method), 240  
`get_widget()` (pylablib.core.gui.widgets.container.QDialogContainer method), 258  
`get_widget()` (pylablib.core.gui.widgets.container.QFrameContainer method), 253  
`get_widget()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 262  
`get_widget()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 270  
`get_widget()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 267  
`get_widget()` (pylablib.core.gui.widgets.container.QTabContainer method), 273  
`get_widget()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 248  
`get_widget()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 292  
`get_widget()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 304  
`get_widget_location()` (in module py-lablib.core.gui.utils), 309  
`get_window_ft_func()` (in module py-lablib.core.dataproc.specfunc), 152  
`get_window_func()` (in module py-lablib.core.dataproc.specfunc), 151  
`get_work_hours()` (py-lablib.devices.Hubner.Cobolt.Cobolt method), 630  
`get_work_hours()` (py-lablib.devices.LaserQuantum.base.Finesse method), 683  
`get_work_hours()` (py-lablib.devices.LighthousePhotonics.base.SproutG method), 690  
`get_work_hours()` (py-lablib.devices.Toptica.ibeam.TopicalBeam method), 969  
`get_x_column()` (in module py-lablib.core.dataproc.utils), 163  
`get_y_column()` (in module py-lablib.core.dataproc.utils), 163  
`getargsfrom()` (in module py-lablib.core.utils.functions), 422  
`getattr_call()` (in module py-lablib.core.utils.functions), 422  
`getattr_multivar()` (in module py-lablib.core.utils.general), 425  
`getdefault()` (in module py-lablib.core.utils.funcargparse), 419  
`goto_zero_order()` (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546  
`gpio` (pylablib.devices.Standa.base.TFullState attribute), 877  
`grab()` (pylablib.devices.AlliedVision.Bonito.BonitoIMACamera method), 517  
`grab()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 511  
`grab()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 532  
`grab()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 542  
`grab()` (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 582  
`grab()` (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 593  
`grab()` (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 589  
`grab()` (pylablib.devices.DCAM.DCAM.DCAMCamera method), 619  
`grab()` (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 644  
`grab()` (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 639  
`grab()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 660  
`grab()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 654

- `grab()` (`pylablib.devices.interface.camera.IAttributeCamera` attribute), 781  
     method), 998 `GrabberClass` (`pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera` attribute), 513
- `grab()` (`pylablib.devices.interface.camera.IBinROICamera` attribute), 513  
     method), 1017 `GrabberClass` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` attribute), 508
- `grab()` (`pylablib.devices.interface.camera.ICamera` attribute), 508  
     method), 993 `GrabberClass` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus` attribute), 782
- `grab()` (`pylablib.devices.interface.camera.IExposureCamera` attribute), 782  
     method), 1007 `GrabberClass` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusB` attribute), 805
- `grab()` (`pylablib.devices.interface.camera.IGrabberAttributeCamera` attribute), 805  
     method), 1003 `GrabberClass` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusI` attribute), 788
- `grab()` (`pylablib.devices.interface.camera.IROICamera` attribute), 788  
     method), 1012 `GrabberClass` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusS` attribute), 797
- `grab()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera` attribute), 797  
     method), 712 `gui_thread_method()` (in module `py-`  
     `pylablib.core.thread.controller`), 342
- `grab()` (`pylablib.devices.PCO.SC2.PCOSC2Camera` attribute), 342  
     method), 761 `gui_values_path` (in module `py-`  
     `pylablib.core.gui.widgets.container.TChild` attribute), 235
- `grab()` (`pylablib.devices.Photometrics.pvcam.PvcamCamera` attribute), 235  
     method), 777 `GUIValueSet` (class in `pylablib.core.gui.value_handling`), 326
- `grab()` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus` attribute), 326  
     method), 785 `GUIValuesIndicatorsSet` (class in `py-`  
     `pylablib.core.gui.value_handling`), 328
- `grab()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera` attribute), 328  
     method), 792
- H**
- `grab()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera` attribute), 151  
     method), 802 `hamming_w()` (in module `py-`  
     `pylablib.core.dataproc.specfunc`), 152
- `grab()` (`pylablib.devices.PrincetonInstruments.picam.PicamCamera` attribute), 152  
     method), 831 `hamming_w_ft()` (in module `py-`  
     `pylablib.core.dataproc.specfunc`), 152
- `grab()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera` attribute), 151  
     method), 851 `ham_w()` (in module `pylablib.core.dataproc.specfunc`), 151
- `grab()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` attribute), 151  
     method), 846 `ham_w_ft()` (in module `py-`  
     `pylablib.core.dataproc.specfunc`), 152
- `grab()` (`pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera` attribute), 152  
     method), 909 `has_arg()` (`pylablib.core.dataproc.callable.FunctionCallable` attribute), 132
- `grab()` (`pylablib.devices.uc480.uc480.UC480Camera` attribute), 132  
     method), 1029 `has_arg()` (`pylablib.core.dataproc.callable.ICallable` attribute), 129
- `grab_continuous()` (`pylablib.devices.Tektronix.base.DPO2000` attribute), 129  
     method), 897 `has_arg()` (`pylablib.core.dataproc.callable.JoinedCallable` attribute), 131
- `grab_continuous()` (`pylablib.devices.Tektronix.base.ITektronixScope` attribute), 131  
     method), 882 `has_arg()` (`pylablib.core.dataproc.callable.MethodCallable` attribute), 133
- `grab_continuous()` (`pylablib.devices.Tektronix.base.TDS2000` attribute), 133  
     method), 891 `has_arg()` (`pylablib.core.dataproc.callable.MultiplexedCallable` attribute), 130
- `grab_single()` (`pylablib.devices.Tektronix.base.DPO2000` attribute), 130  
     method), 897 `has_calls()` (`pylablib.core.thread.callsync.QQueueLengthLimitScheduler` attribute), 337
- `grab_single()` (`pylablib.devices.Tektronix.base.ITektronixScope` attribute), 337  
     method), 881 `has_calls()` (`pylablib.core.thread.callsync.QQueueScheduler` attribute), 335
- `grab_single()` (`pylablib.devices.Tektronix.base.TDS2000` attribute), 335  
     method), 891 `has_calls()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` attribute), 338
- `grabber_info` (`pylablib.devices.AlliedVision.Bonito.TDeviceInfo` attribute), 378  
     method), 507 `has_entry()` (`pylablib.core.utils.dictionary.Dictionary` attribute), 378
- `grabber_info` (`pylablib.devices.PhotonFocus.PhotonFocus.TDeviceInfo` attribute), 378  
     method), 406 `has_entry()` (`pylablib.core.utils.dictionary.DictionaryPointer` attribute), 389
- `grabber_info` (`pylablib.devices.PhotonFocus.PhotonFocus.TDeviceInfo` attribute), 389  
     method), 406 `has_entry()` (`pylablib.core.utils.dictionary.FilterTree` attribute), 406

[has\\_entry\(\)](#) (`pylablib.core.utils.dictionary.PrefixTree` method), 398  
[has\\_methods\(\)](#) (in module `pylablib.core.gui.value_handling`), 311  
[head](#) (`pylablib.devices.LaserQuantum.base.TTemperatures` attribute), 682  
[head\\_model](#) (`pylablib.devices.Andor.AndorSDK2.TDeviceInfo` attribute), 523  
[height](#) (`pylablib.core.dataproc.feature.Peak` attribute), 135  
[height](#) (`pylablib.devices.interface.camera.TFrameSize` attribute), 989  
[hide\\_tab\(\)](#) (`pylablib.core.gui.widgets.container.QTabContainer` method), 272  
[HIDError](#), 196  
[HIDDevice](#) (class in `pylablib.core.devio.hid`), 194  
[HIDDevice.Reader](#) (class in `pylablib.core.devio.hid`), 195  
[HIDDeviceBackend](#) (class in `pylablib.core.devio.comm_backend`), 186  
[HIDLibError](#), 196  
[HIDTimeoutError](#), 196  
[high\\_pass\\_filter\(\)](#) (in module `pylablib.core.dataproc.filters`), 137  
[high\\_thresh](#) (`pylablib.devices.Pfeiffer.base.TTPG260Switch` attribute), 764  
[high\\_value](#) (`pylablib.devices.Lakeshore.base.TLakeshore218Analog` attribute), 671  
[high\\_value](#) (`pylablib.devices.Lakeshore.base.TLakeshore370AnalogSettings` attribute), 677  
[hold\\_current](#) (`pylablib.devices.Standa.base.TPowerParams` attribute), 877  
[hold\\_time](#) (`pylablib.devices.SmarAct.MCS2.TCLMoveParams` attribute), 869  
[home](#) (`pylablib.devices.Andor.Shamrock.TGratingInfo` attribute), 545  
[home\(\)](#) (`pylablib.devices.Arcus.performax.Performax2EXStage` method), 558  
[home\(\)](#) (`pylablib.devices.Arcus.performax.Performax4EXStage` method), 554  
[home\(\)](#) (`pylablib.devices.Arcus.performax.PerformaxDMXJSStage` method), 561  
[home\(\)](#) (`pylablib.devices.OZOptics.base.DD100` method), 743  
[home\(\)](#) (`pylablib.devices.OZOptics.base.TF100` method), 741  
[home\(\)](#) (`pylablib.devices.SmarAct.MCS2.MCS2` method), 872  
[home\(\)](#) (`pylablib.devices.Standa.base.Standa8SMC` method), 879  
[home\(\)](#) (`pylablib.devices.Thorlabs.elliptec.ElliptecMotor` method), 914  
[home\(\)](#) (`pylablib.devices.Thorlabs.kinesis.KinesisMotor` method), 929  
[home\(\)](#) (`pylablib.devices.Trinamic.base.TMCM1110` method), 974  
[home\(\)](#) (`pylablib.devices.Trinamic.base.TMCMx110` method), 978  
[home\\_direction](#) (`pylablib.devices.Thorlabs.kinesis.THomeParams` attribute), 919  
[home\\_position](#) (`pylablib.devices.Thorlabs.kinesis.TPolCtlParams` attribute), 919  
[hour](#) (`pylablib.devices.uc480.uc480.TTimestamp` attribute), 1024  
[hrng](#) (`pylablib.devices.PrincetonInstruments.picam.TROIConstraints` attribute), 825  
[HubnerBackendError](#), 633  
[HubnerError](#), 633  
[huge\\_error\(\)](#) (in module `pylablib.core.dataproc.fitting`), 144  
[hw\\_kind\\_ccw](#) (`pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams` attribute), 920  
[hw\\_kind\\_cw](#) (`pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams` attribute), 920  
[hw\\_swapped](#) (`pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams` attribute), 920  
[hw\\_type](#) (`pylablib.devices.Thorlabs.kinesis.TDeviceInfo` attribute), 916  
[hw\\_type](#) (`pylablib.devices.Thorlabs.elliptec.TDeviceInfo` attribute), 911  
[hw\\_type](#) (`pylablib.devices.Thorlabs.kinesis.TDeviceInfo` attribute), 916  
[I](#) (`pylablib.devices.Sirah.Matisse.TSlowpiezoCtlParameters` attribute), 855  
[I](#) (`pylablib.devices.Sirah.Matisse.TThinectCtlParameters` attribute), 855  
[I](#) (`pylablib.devices.Thorlabs.kinesis.TQuadDetectorPIDParams` attribute), 942  
[i\(\)](#) (`pylablib.core.dataproc.ctransform_fallback.CLinear2DTransform` method), 134  
[i\(\)](#) (`pylablib.core.dataproc.transform.Indexed2DTransform` method), 162  
[i\(\)](#) (`pylablib.core.dataproc.transform.LinearTransform` method), 161  
[i\(\)](#) (`pylablib.core.devio.interface.CombinedParameterClass` method), 202  
[i\(\)](#) (`pylablib.core.devio.interface.EnumParameterClass` method), 201  
[i\(\)](#) (`pylablib.core.devio.interface.FunctionParameterClass` method), 201  
[i\(\)](#) (`pylablib.core.devio.interface.ICheckingParameterClass` method), 198



- i() (pylablib.core.devio.interface.IEnumParameterClass method), 200
- i() (pylablib.core.devio.interface.IParameterClass method), 197
- i() (pylablib.core.devio.interface.RangeParameterClass method), 198
- I1DWrapper (class in pylablib.core.dataproc.table\_wrap), 152
- I1DWrapper.Accessor (class in pylablib.core.dataproc.table\_wrap), 152
- I2DWrapper (class in pylablib.core.dataproc.table\_wrap), 156
- IArduinoDevice (class in pylablib.devices.Arduino.base), 564
- IAttributeCamera (class in pylablib.devices.interface.camera), 995
- ib\_get\_default\_address() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_get\_default\_address() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- ib\_get\_reg() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_get\_reg() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- ib\_scan\_devices() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_scan\_devices() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- ib\_set\_default\_address() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_set\_default\_address() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- ib\_set\_reg() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_set\_reg() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- ib\_using\_address() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 726
- ib\_using\_address() (pylablib.devices.NKT.interbus.InterbusSystem method), 734
- IBinaryOutputFileFormat (class in pylablib.core.fileio.savefile), 227
- IBinROICamera (class in pylablib.devices.interface.camera), 1015
- IBonitoCamera (class in pylablib.devices.AlliedVision.Bonito), 507
- IBoolValueHandler (class in pylablib.core.gui.value\_handling), 319
- ICallable (class in pylablib.core.dataproc.callable), 129
- ICallable.NamesBoundCall (class in pylablib.core.dataproc.callable), 130
- ICamera (class in pylablib.devices.interface.camera), 990
- ICEBlocDevice (class in pylablib.devices.M2.base), 695
- ICheckingParameterClass (class in pylablib.core.devio.interface), 197
- ICommBackendWrapper (class in pylablib.core.devio.comm\_backend), 192
- id (pylablib.core.utils.ipc.TPipeMsg attribute), 435
- id (pylablib.devices.Newport.picomotor.TDeviceInfo attribute), 736
- id (pylablib.devices.Ophir.base.TDeviceInfo attribute), 751
- id (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987
- IDataLocation (class in pylablib.core.fileio.location), 218
- IDevice (class in pylablib.core.devio.interface), 196
- IDeviceCommBackend (class in pylablib.core.devio.comm\_backend), 170
- IDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 204
- idreg (pylablib.devices.BitFlow.BitFlow.TDeviceInfo attribute), 585
- idx (pylablib.devices.BitFlow.BitFlow.TDeviceInfo attribute), 585
- idx (pylablib.devices.Mightex.MightexSSeries.TCameraInfo attribute), 707
- IEnumParameterClass (class in pylablib.core.devio.interface), 199
- IExposureCamera (class in pylablib.devices.interface.camera), 1005
- IExternalFileDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 208
- IExternalTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 206
- IFileSystemDataLocation (class in pylablib.core.fileio.location), 219
- IGenWrapper (class in pylablib.core.dataproc.table\_wrap), 152
- IGrabberAttributeCamera (class in pylablib.devices.interface.camera), 1000
- IIndex (class in pylablib.core.utils.indexing), 433
- IIndicatorHandler (class in pylablib.core.gui.value\_handling), 325
- IInputFileFormat (class in pylablib.core.fileio.loadfile), 210
- IInterbusModule (class in pylablib.devices.NKT.interbus), 727

- [IIPCChannel \(class in pylablib.core.utils.ipc\)](#), 435  
[iir\\_apply\\_complex\(\)](#) (in module `pylablib.core.dataproc.iir_transform`), 147  
[ilabels \(pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute\)](#), 535  
[ilabels \(pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute\)](#), 577  
[ilabels \(pylablib.devices.DCAM.DCAM.DCAMAttribute attribute\)](#), 614  
[ilabels \(pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute\)](#), 650  
[ilabels \(pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute\)](#), 770  
[ilabels \(pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute\)](#), 781  
[ilabels \(pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute\)](#), 827  
[ilabels \(pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute\)](#), 840  
[IMAQCamera \(class in pylablib.devices.IMAQ.IMAQ\)](#), 641  
[IMAQdxAttribute \(class in `pylablib.devices.IMAQdx.IMAQdx`\)](#), 649  
[IMAQdxCamera \(class in `pylablib.devices.IMAQdx.IMAQdx`\)](#), 650  
[IMAQdxCamera.CallbackManager \(class in `pylablib.devices.IMAQdx.IMAQdx`\)](#), 652  
[IMAQFrameGrabber \(class in `pylablib.devices.IMAQ.IMAQ`\)](#), 633  
[implemented \(pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute\)](#), 534  
[implemented \(pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute\)](#), 576  
[IMultiaxisStage \(class in `pylablib.devices.interface.stage`\)](#), 1021  
[in\\_use \(pylablib.devices.uc480.uc480.TCameraInfo attribute\)](#), 1023  
[inc \(pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute\)](#), 576  
[inc \(pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute\)](#), 650  
[inc \(pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute\)](#), 770  
[inc \(pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute\)](#), 826  
[inc \(pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute\)](#), 840  
[inc\(\) \(pylablib.devices.interface.camera.FrameNotifier method\)](#), 995  
[ind \(pylablib.core.gui.value\\_handling.GUIValues.IndicatorsSet attribute\)](#), 328  
[index \(pylablib.devices.Attocube.anc350.ANC350.Reply attribute\)](#), 570  
[index \(pylablib.devices.Attocube.anc350.ANC350.Telegram attribute\)](#), 570  
[index \(pylablib.devices.Windows.joystick.TJoystickEvent attribute\)](#), 987  
[index \(pylablib.devices.Windows.joystick.TJoystickEventEx attribute\)](#), 987  
[index\\_to\\_value\(\) \(pylablib.core.gui.widgets.button\\_selector.ButtonSelector method\)](#), 233  
[index\\_to\\_value\(\) \(pylablib.core.gui.widgets.combo\\_box.ComboBox method\)](#), 234  
[Indexed2DTransform \(class in `pylablib.core.dataproc.transform`\)](#), 162  
[indicator \(pylablib.core.gui.widgets.param\\_table.ParamTable.ParamRow attribute\)](#), 285  
[indicator\\_handler \(pylablib.core.gui.widgets.param\\_table.ParamTable.ParamRow attribute\)](#), 285  
[individual \(pylablib.core.utils.dictionary.DictionaryIntersection attribute\)](#), 385  
[infinite\\_list \(class in `pylablib.core.utils.numerical`\)](#), 444  
[infinite\\_list.counter \(class in `pylablib.core.utils.numerical`\)](#), 444  
[info \(pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute\)](#), 839  
[init\\_amp\\_mode\(\) \(pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method\)](#), 526  
[init\\_result \(pylablib.devices.utils.load\\_lib.TLibraryOpenResult attribute\)](#), 1033  
[initial\\_guess\(\) \(pylablib.core.dataproc.fitting.Fitter method\)](#), 143  
[InlineTable \(class in `pylablib.core.fileio.loadfile\_utils`\)](#), 216  
[InlineTableDictionaryEntry \(class in `pylablib.core.fileio.dict\_entry`\)](#), 205  
[insert\(\) \(pylablib.core.dataproc.table\\_wrap.Array1DWrapper method\)](#), 154  
[insert\(\) \(pylablib.core.dataproc.table\\_wrap.Array2DWrapper.ColumnAccess method\)](#), 157  
[insert\(\) \(pylablib.core.dataproc.table\\_wrap.Array2DWrapper.RowAccess method\)](#), 157  
[insert\(\) \(pylablib.core.dataproc.table\\_wrap.DataFrame2DWrapper.ColumnAccess method\)](#), 160  
[insert\(\) \(pylablib.core.dataproc.table\\_wrap.DataFrame2DWrapper.RowAccess method\)](#), 159  
[insert\\_column\(\) \(pylablib.core.gui.widgets.container.IQWidgetContainer method\)](#), 244  
[insert\\_column\(\) \(pylablib.core.gui.widgets.container.QDialogContainer method\)](#), 258  
[insert\\_column\(\) \(pylablib.core.gui.widgets.container.QFrameContainer method\)](#), 258

method), 253

insert\_column() (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 262

insert\_column() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainedWidget method), 267

insert\_column() (py-lablib.core.gui.widgets.container.QWidgetContainer method), 248

insert\_column() (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 281

insert\_column() (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 283

insert\_column() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 294

insert\_column() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 304

insert\_layout\_column() (in module py-lablib.core.gui.utils), 310

insert\_layout\_row() (in module py-lablib.core.gui.utils), 310

insert\_option() (py-lablib.core.gui.widgets.combo\_box.ComboBox method), 235

insert\_row() (pylablib.core.gui.widgets.container.IQWidgetContainer method), 244

insert\_row() (pylablib.core.gui.widgets.container.QDialogContainer method), 258

insert\_row() (pylablib.core.gui.widgets.container.QFrameContainer method), 253

insert\_row() (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 262

insert\_row() (pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainedWidget method), 267

insert\_row() (pylablib.core.gui.widgets.container.QWidgetContainer method), 248

insert\_row() (pylablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 281

insert\_row() (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 283

insert\_row() (pylablib.core.gui.widgets.param\_table.ParamTable method), 294

insert\_row() (pylablib.core.gui.widgets.param\_table.StatusTable method), 304

insert\_status\_line() (in module py-lablib.devices.interface.camera), 1020

install\_if\_older() (in module py-lablib.core.utils.module), 438

InstekAFG2000 (class in py-lablib.devices.AWG.specific), 480

InstekAFG2225 (class in py-lablib.devices.AWG.specific), 474

int2bits() (in module py-lablib.core.utils.strpack), 453

int2bytes() (in module py-lablib.core.utils.strpack), 454

integer\_distance() (in module py-lablib.core.utils.numerical), 444

IntegerFormatter (class in py-lablib.core.gui.formatter), 307

integrate() (in module py-lablib.core.dataproc.filters), 444

InterbusBackendError, 725

InterbusError, 725

InterbusSystem (class in py-lablib.devices.NKT.interbus), 733

interface (pylablib.devices.IMAQ.Q.TDeviceInfo attribute), 633

interface (pylablib.devices.PCO.SC2.TDeviceInfo attribute), 754

interface (pylablib.devices.PrincetonInstruments.picam.TCameraInfo attribute), 824

interface (pylablib.devices.PrincetonInstruments.picam.TDeviceInfo attribute), 827

interpolate1D() (in module py-lablib.core.dataproc.interpolate), 149

interpolate1D\_func() (in module py-lablib.core.dataproc.interpolate), 148

interpolate2D() (in module py-lablib.core.dataproc.interpolate), 149

interpolate\_trace() (in module py-lablib.core.dataproc.interpolate), 150

interpolateND() (in module py-lablib.core.dataproc.interpolate), 149

InterruptException, 370

InterruptExceptionStop, 370

intersect() (pylablib.core.dataproc.image.ROI class method), 164

intersect() (pylablib.core.dataproc.utils.Range method), 164

inverse\_fourier\_transform() (in module py-lablib.core.dataproc.fourier), 145

invert() (pylablib.core.dataproc.ctransform\_fallback.CLinear2DTransform method), 161

invert\_dict() (in module py-lablib.core.utils.general), 426

inverted() (pylablib.core.dataproc.transform.Indexed2DTransform method), 162

inverted() (pylablib.core.dataproc.transform.LinearTransform method), 161

io1\_oper\_mode (pylablib.devices.Thorlabs.kinesis.TFlipperParameters attribute), 924

io1\_pulse\_width (py-lablib.devices.Thorlabs.kinesis.TFlipperParameters attribute), 924

attribute), 924  
 io1\_sig\_mode (pylablib.devices.Thorlabs.kinesis.TFlipperParameterClass attribute), 924  
 io2\_oper\_mode (pylablib.devices.Thorlabs.kinesis.TFlipperParameterClass attribute), 924  
 io2\_pulse\_width (pylablib.devices.Thorlabs.kinesis.TFlipperParameterClass attribute), 924  
 io2\_sig\_mode (pylablib.devices.Thorlabs.kinesis.TFlipperParameterClass attribute), 924  
 io\_status (pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024  
 IObjectCall (class in pylablib.core.utils.functions), 423  
 IObjectProperty (class in pylablib.core.utils.functions), 423  
 IOutputFileFormat (class in pylablib.core.fileio.savefile), 224  
 IParameterClass (class in pylablib.core.devio.interface), 197  
 IPhotonFocusCamera (class in pylablib.devices.PhotonFocus.PhotonFocus), 781  
 IQContainer (class in pylablib.core.gui.widgets.container), 236  
 IQLayoutManagedWidget (class in pylablib.core.gui.widgets.layout\_manager), 279  
 IQWidgetContainer (class in pylablib.core.gui.widgets.container), 241  
 IROICamera (class in pylablib.devices.interface.camera), 1010  
 is\_accessory\_present() (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548  
 is\_acquisition\_setup() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 517  
 is\_acquisition\_setup() (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 511  
 is\_acquisition\_setup() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 532  
 is\_acquisition\_setup() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 542  
 is\_acquisition\_setup() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 582  
 is\_acquisition\_setup() (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 594  
 is\_acquisition\_setup() (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 589  
 is\_acquisition\_setup() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 620  
 is\_acquisition\_setup() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 644  
 is\_acquisition\_setup() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 639  
 is\_acquisition\_setup() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 660  
 is\_acquisition\_setup() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 655  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.IAttributeCamera method), 998  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.IBinROICamera method), 1017  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.ICamera method), 990  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.IExposureCamera method), 1008  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1003  
 is\_acquisition\_setup() (pylablib.devices.interface.camera.IROICamera method), 1012  
 is\_acquisition\_setup() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 712  
 is\_acquisition\_setup() (pylablib.devices.PCO.SC2.PCOSC2Camera method), 761  
 is\_acquisition\_setup() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 777  
 is\_acquisition\_setup() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 786  
 is\_acquisition\_setup() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 809  
 is\_acquisition\_setup() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 793  
 is\_acquisition\_setup() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 809



method), 802

is\_acquisition\_setup() (py-lablib.devices.PrincetonInstruments.picam.PicamCamera method), 831

is\_acquisition\_setup() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera method), 851

is\_acquisition\_setup() (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 846

is\_acquisition\_setup() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 909

is\_acquisition\_setup() (py-lablib.devices.uc480.uc480.UC480Camera method), 1029

is\_analog\_modulation\_enabled() (py-lablib.devices.Hubner.Cobolt.Cobolt method), 631

is\_ascending() (in module py-lablib.core.dataproc.utils), 162

is\_ascii() (pylablib.core.devio.data\_format.DataFormat method), 193

is\_at\_zero\_order() (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546

is\_aurorange\_enabled() (py-lablib.devices.Thorlabs.misc.GenericPM method), 946

is\_aurorange\_enabled() (py-lablib.devices.Thorlabs.misc.PM160 method), 952

is\_aurorange\_enabled() (py-lablib.devices.Voltcraft.multimeter.VC7055 method), 981

is\_autostart\_enabled() (py-lablib.devices.Hubner.Cobolt.Cobolt method), 630

is\_batch\_job\_running() (py-lablib.core.thread.controller.QTaskThread method), 353

is\_bool\_array() (in module py-lablib.core.utils.indexing), 433

is\_branch\_path() (py-lablib.core.utils.dictionary.Dictionary method), 378

is\_branch\_path() (py-lablib.core.utils.dictionary.DictionaryPointer method), 389

is\_branch\_path() (py-lablib.core.utils.dictionary.FilterTree method), 406

is\_branch\_path() (py-lablib.core.utils.dictionary.PrefixTree method), 398

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.DictEntryParser method), 203

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.ExpandedContainerDictionaryEntry class method), 210

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.ExternalBinTableDictionaryEntry class method), 208

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.ExternalNumpyDictionaryEntry class method), 210

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.ExternalTextTableDictionaryEntry class method), 207

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.IDictionaryEntry class method), 204

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.IExternalFileDictionaryEntry class method), 209

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.IExternalTableDictionaryEntry class method), 206

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.InlineTableDictionaryEntry class method), 206

is\_branch\_valid() (py-lablib.core.fileio.dict\_entry.ITableDictionaryEntry class method), 205

is\_burst\_enabled() (py-lablib.devices.AWG.generic.GenericAWG method), 457

is\_burst\_enabled() (py-lablib.devices.AWG.specific.Agilent33220A method), 470

is\_burst\_enabled() (py-lablib.devices.AWG.specific.Agilent33500 method), 464

is\_burst\_enabled() (py-lablib.devices.AWG.specific.InstekAFG2000 method), 483

is\_burst\_enabled() (py-lablib.devices.AWG.specific.InstekAFG2225 method), 477

is\_burst\_enabled() (py-lablib.devices.AWG.specific.RigolDG1000 method), 501

is\_burst\_enabled() (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 489

is\_burst\_enabled() (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 489

method), 495

is\_call\_done() (pylablib.core.thread.callsync.QCallResultSyncCallback.reenabled() (py-  
method), 330 lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera

is\_call\_done() (pylablib.core.thread.callsync.QDirectResultSyncCallback.reenabled() (py-  
method), 331 method), 906

is\_CFR\_enabled() (py- lablib.core.fileio.dict\_entry.DictEntryBuilder  
lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera.method), 203

method), 783 is\_data\_valid() (py-  
is\_CFR\_enabled() (py- lablib.core.fileio.dict\_entry.ExpandedContainerDictionaryEntry  
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera.method), 210

method), 809 is\_data\_valid() (py-  
is\_CFR\_enabled() (py- lablib.core.fileio.dict\_entry.ExternalBinTableDictionaryEntry  
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera.method), 208

method), 793 is\_data\_valid() (py-  
is\_CFR\_enabled() (py- lablib.core.fileio.dict\_entry.ExternalNumpyDictionaryEntry  
lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera.method), 210

method), 802 is\_data\_valid() (py-  
is\_channel\_enabled() (py- lablib.core.fileio.dict\_entry.ExternalTextTableDictionaryEntry  
lablib.devices.Tektronix.base.DPO2000 class method), 207

method), 898 is\_data\_valid() (py-  
is\_channel\_enabled() (py- lablib.core.fileio.dict\_entry.IDictionaryEntry  
lablib.devices.Tektronix.base.ITektronixScope class method), 204

method), 883 is\_data\_valid() (py-  
is\_channel\_enabled() (py- lablib.core.fileio.dict\_entry.IExternalFileDictionaryEntry  
lablib.devices.Tektronix.base.TDS2000 class method), 209

method), 891 is\_data\_valid() (py-  
is\_channel\_enabled() (py- lablib.core.fileio.dict\_entry.IExternalTableDictionaryEntry  
lablib.devices.Thorlabs.kinesis.KinesisPiezoController class method), 206

method), 938 is\_data\_valid() (py-  
is\_channel\_enabled() (py- lablib.core.fileio.dict\_entry.InlineTableDictionaryEntry  
lablib.devices.Topica.ibeam.TopicalBeam class method), 206

method), 969 is\_data\_valid() (py-  
is\_command (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute lablib.core.fileio.dict\_entry.ITableDictionaryEntry  
attribute), 535 class method), 205

is\_command (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera.is\_descending() (in module py-  
attribute), 780 lablib.core.dataproc.utils), 162

is\_connected() (pylablib.core.utils.net.ClientSocket is\_dict\_entry\_branch() (in module py-  
method), 442 lablib.core.fileio.dict\_entry), 203

is\_connected() (pylablib.devices.Attocube.anc350.ANC350.is\_dictionary() (in module py-  
method), 571 lablib.core.utils.dictionary), 376

is\_continuous() (py- is\_dictionary() (py-  
lablib.devices.Tektronix.base.DPO2000 lablib.core.utils.dictionary.Dictionary static  
method), 898 method), 377

is\_continuous() (py- is\_dictionary() (py-  
lablib.devices.Tektronix.base.ITektronixScope lablib.core.utils.dictionary.DictionaryPointer  
method), 882 static method), 390

is\_continuous() (py- is\_dictionary() (py-  
lablib.devices.Tektronix.base.TDS2000 lablib.core.utils.dictionary.FilterTree static  
method), 891 method), 406

is\_convertible() (in module py- is\_dictionary() (py-  
lablib.core.utils.string), 452 lablib.core.utils.dictionary.PrefixTree static

is\_cooler\_on() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera.is\_diffuser\_in() (py-  
method), 524 method), 398

is\_cooler\_on() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera lablib.devices.Ophir.base.VegaPowerMeter

method), 753

`is_digital_modulation_enabled()` (pylablib.devices.Hubner.Cobolt.Cobolt method), 631

`is_drift_compensation_enabled()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 816

`is_enabled()` (pylablib.devices.Arcus.performax.Performax2EXStage method), 558

`is_enabled()` (pylablib.devices.Arcus.performax.Performax4EXStage method), 553

`is_enabled()` (pylablib.devices.Arcus.performax.PerformaxDMXJSAS method), 560

`is_enabled()` (pylablib.devices.Attocube.anc300.ANC300 method), 567

`is_enabled()` (pylablib.devices.Attocube.anc350.ANC350 method), 571

`is_enabled()` (pylablib.devices.Hubner.Cobolt.Cobolt method), 631

`is_enabled()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 672

`is_enabled()` (pylablib.devices.LaserQuantum.base.Finesse method), 683

`is_enabled()` (pylablib.devices.LighthousePhotonics.base.SproutG method), 690

`is_enabled()` (pylablib.devices.Pfeiffer.base.TPG260 method), 765

`is_enabled()` (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 969

`is_fastpiezo_locked()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 860

`is_filter_in()` (pylablib.devices.Ophir.base.VegaPowerM2 method), 753

`is_filter_present()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547

`is_fine_tuning()` (pylablib.devices.M2.emm.EMM method), 698

`is_flipper_present()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547

`is_focus_mirror_present()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548

`is_frame_transfer_enabled()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 528

`is_free()` (pylablib.core.fileio.location.FolderFileSystemDataLocation method), 222

`is_free()` (pylablib.core.fileio.location.IDataLocation method), 218

`is_free()` (pylablib.core.fileio.location.IFileSystemDataLocation method), 219

`is_free()` (pylablib.core.fileio.location.OpenedFileLocation method), 219

`is_free()` (pylablib.core.fileio.location.PrefixedFileSystemDataLocation method), 221

`is_free()` (pylablib.core.fileio.location.SingleFileSystemDataLocation method), 220

`is_grabbing()` (pylablib.devices.Tektronix.base.DPO2000 method), 898

`is_grabbing()` (pylablib.devices.Tektronix.base.ITektronixScope method), 882

`is_grabbing()` (pylablib.devices.Tektronix.base.TDS2000 method), 891

`is_gui_running()` (in module pylablib.core.thread.threadprop), 370

`is_gui_thread()` (in module pylablib.core.thread.threadprop), 370

`is_handled_widget()` (in module pylablib.core.gui.value\_handling), 325

`is_homed()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 929

`is_homing()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 929

`is_homing()` (pylablib.devices.Trinamic.base.TMCM1110 method), 974

`is_homing()` (pylablib.devices.Trinamic.base.TMCMx110 method), 978

`is_in_controlled()` (pylablib.core.thread.controller.QTaskThread method), 358

`is_in_controlled()` (pylablib.core.thread.controller.QThreadController method), 349

`is_integer()` (in module pylablib.core.gui.formatter), 307

`is_iris_present()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547

`is_layout_column_empty()` (in module pylablib.core.gui.utils), 310

`is_layout_row_empty()` (in module pylablib.core.gui.utils), 310

`is_leaf_path()` (pylablib.core.utils.dictionary.Dictionary method), 378

`is_leaf_path()` (pylablib.core.utils.dictionary.DictionaryPointer method), 390

`is_leaf_path()` (pylablib.core.utils.dictionary.FilterTree method), 407

`is_leaf_path()` (pylablib.core.utils.dictionary.PrefixTree method), 399

`is_led_enabled()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 906

`is_linear()` (in module pylablib.core.dataproc.utils), 163

`is_looping()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera.SchmalzDp075r`  
`method`), 580

`is_looping()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera978`  
`method`), 710

`is_mandatory_arg()` (`py-`  
`lablib.core.dataproc.callable.FunctionCallable`  
`method`), 132

`is_mandatory_arg()` (`py-`  
`lablib.core.dataproc.callable.ICallable`  
`method`), 130

`is_mandatory_arg()` (`py-`  
`lablib.core.dataproc.callable.JoinedCallable`  
`method`), 132

`is_mandatory_arg()` (`py-`  
`lablib.core.dataproc.callable.MethodCallable`  
`method`), 133

`is_mandatory_arg()` (`py-`  
`lablib.core.dataproc.callable.MultiplexedCallable`  
`method`), 131

`is_measurement_running()` (`py-`  
`lablib.devices.HighFinesse.wlm.WLM` `method`),  
 626

`is_metadata_enabled()` (`py-`  
`lablib.devices.Andor.AndorSDK3.AndorSDK3Camera`  
`method`), 538

`is_metadata_enabled()` (`py-`  
`lablib.devices.Photometrics.pvcam.PvcamCamera`  
`method`), 773

`is_metadata_enabled()` (`py-`  
`lablib.devices.PrincetonInstruments.picam.PicamCamera`  
`method`), 828

`is_moving()` (`pylablib.devices.Arcus.performax.Performax2EXStag`  
`method`), 559

`is_moving()` (`pylablib.devices.Arcus.performax.Performax4EXStag`  
`method`), 554

`is_moving()` (`pylablib.devices.Arcus.performax.PerformaxDMXJSA`  
`method`), 561

`is_moving()` (`pylablib.devices.Attocube.anc300.ANC300`  
`method`), 568

`is_moving()` (`pylablib.devices.Attocube.anc350.ANC350`  
`method`), 571

`is_moving()` (`pylablib.devices.Newport.picomotor.Picomotor8742`  
`method`), 738

`is_moving()` (`pylablib.devices.SmarAct.MCS2.MCS2`  
`method`), 870

`is_moving()` (`pylablib.devices.SmarAct.scu3d.SCU3D`  
`method`), 875

`is_moving()` (`pylablib.devices.Standa.base.Standa8SMC`  
`method`), 878

`is_moving()` (`pylablib.devices.Thorlabs.kinesis.KinesisMotor`  
`method`), 930

`is_moving()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor`  
`method`), 935

`is_moving()` (`pylablib.devices.Trinamic.base.TMCM1110`  
`method`), 545

`is_moving()` (`pylablib.devices.Trinamic.base.TMCMx110`  
`method`), 545

`is_nir_boost_enabled()` (`py-`  
`lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera`  
`method`), 906

`is_ocp_enabled()` (`py-`  
`lablib.devices.Rigol.power_supply.DP1116A`  
`method`), 835

`is_online_enabled()` (`py-`  
`lablib.devices.PhysikInstrumente.base.GenericPIController`  
`method`), 815

`is_online_enabled()` (`py-`  
`lablib.devices.PhysikInstrumente.base.PIE515`  
`method`), 819

`is_online_enabled()` (`py-`  
`lablib.devices.PhysikInstrumente.base.PIE516`  
`method`), 818

`is_opened()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend`  
`method`), 179

`is_opened()` (`pylablib.core.devio.comm_backend.HIDeviceBackend`  
`method`), 187

`is_opened()` (`pylablib.core.devio.comm_backend.ICommBackendWrapper`  
`method`), 193

`is_opened()` (`pylablib.core.devio.comm_backend.IDeviceCommBackend`  
`method`), 171

`is_opened()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend`  
`method`), 182

`is_opened()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend`  
`method`), 184

`is_opened()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend`  
`method`), 189

`is_opened()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend`  
`method`), 176

`is_opened()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend`  
`method`), 173

`is_opened()` (`pylablib.core.devio.hid.HIDevice`  
`method`), 194

`is_opened()` (`pylablib.core.devio.interface.IDevice`  
`method`), 196

`is_opened()` (`pylablib.core.devio.SCPI.SCPIDevice`  
`method`), 168

`is_opened()` (`pylablib.devices.Agilent.pressure.XGS600`  
`method`), 507

`is_opened()` (`pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera`  
`method`), 517

`is_opened()` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera`  
`method`), 511

`is_opened()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`method`), 524

`is_opened()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera`  
`method`), 537

`is_opened()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph`  
`method`), 545



`is_opened()` (pylablib.devices.Arcus.performax.GenericPeriscope.is\_opened method), 551  
`is_opened()` (pylablib.devices.Arcus.performax.Performax250.is\_opened method), 559  
`is_opened()` (pylablib.devices.Arcus.performax.Performax300.is\_opened method), 556  
`is_opened()` (pylablib.devices.Arcus.performax.Performax350.is\_opened method), 562  
`is_opened()` (pylablib.devices.Arduino.base.IArduinoDevice.is\_opened method), 565  
`is_opened()` (pylablib.devices.Attocube.anc300.ANC300.is\_opened method), 569  
`is_opened()` (pylablib.devices.Attocube.anc350.ANC350.is\_opened method), 573  
`is_opened()` (pylablib.devices.AWG.generic.GenericAWG.is\_opened method), 459  
`is_opened()` (pylablib.devices.AWG.specific.Agilent33220A.is\_opened method), 470  
`is_opened()` (pylablib.devices.AWG.specific.Agilent33500.is\_opened method), 464  
`is_opened()` (pylablib.devices.AWG.specific.InstekAFG2000.is\_opened method), 483  
`is_opened()` (pylablib.devices.AWG.specific.InstekAFG2215.is\_opened method), 477  
`is_opened()` (pylablib.devices.AWG.specific.RigolDG1000.is\_opened method), 501  
`is_opened()` (pylablib.devices.AWG.specific.RSInstekAFG1100.is\_opened method), 489  
`is_opened()` (pylablib.devices.AWG.specific.TektronixAFG4100.is\_opened method), 495  
`is_opened()` (pylablib.devices.Basler.pylon.BaslerPylonCamera.is\_opened method), 578  
`is_opened()` (pylablib.devices.BitFlow.BitFlow.BitFlowCamera.is\_opened method), 594  
`is_opened()` (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.is\_opened method), 585  
`is_opened()` (pylablib.devices.Conrad.base.RelayBoard.is\_opened method), 599  
`is_opened()` (pylablib.devices.Cryocon.base.Cryocon1x.is\_opened method), 601  
`is_opened()` (pylablib.devices.Cryomagnetics.base.LM500.is\_opened method), 606  
`is_opened()` (pylablib.devices.Cryomagnetics.base.LM510.is\_opened method), 610  
`is_opened()` (pylablib.devices.DCAM.DCAM.DCAMCamera.is\_opened method), 615  
`is_opened()` (pylablib.devices.ElektroAutomatik.base.PS200B.is\_opened method), 625  
`is_opened()` (pylablib.devices.HighFinesse.wlm.WLM.is\_opened method), 626  
`is_opened()` (pylablib.devices.Hubner.Cobolt.Cobolt.is\_opened method), 632  
`is_opened()` (pylablib.devices.IMAQ.IMAQ.IMAQCamera.is\_opened method), 645  
`is_opened()` (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber.is\_opened method), 634  
`is_opened()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.is\_opened method), 660  
`is_opened()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.is\_opened method), 651  
`is_opened()` (pylablib.devices.interface.camera.IAttributeCamera.is\_opened method), 998  
`is_opened()` (pylablib.devices.interface.camera.IBinROICamera.is\_opened method), 1017  
`is_opened()` (pylablib.devices.interface.camera.ICamera.is\_opened method), 994  
`is_opened()` (pylablib.devices.interface.camera.IExposureCamera.is\_opened method), 1008  
`is_opened()` (pylablib.devices.interface.camera.IGrabberAttributeCamera.is\_opened method), 1003  
`is_opened()` (pylablib.devices.interface.camera.IROICamera.is\_opened method), 1013  
`is_opened()` (pylablib.devices.interface.stage.IMultiaxisStage.is\_opened method), 1022  
`is_opened()` (pylablib.devices.interface.stage.IStage.is\_opened method), 1021  
`is_opened()` (pylablib.devices.Keithley.multimeter.Keithley2110.is\_opened method), 669  
`is_opened()` (pylablib.devices.KJL.base.KJL300.is\_opened method), 665  
`is_opened()` (pylablib.devices.Lakeshore.base.Lakeshore218.is\_opened method), 675  
`is_opened()` (pylablib.devices.Lakeshore.base.Lakeshore370.is\_opened method), 680  
`is_opened()` (pylablib.devices.LaserQuantum.base.Finesse.is\_opened method), 684  
`is_opened()` (pylablib.devices.Leybold.base.GenericITR.is\_opened method), 687  
`is_opened()` (pylablib.devices.Leybold.base.ITR90.is\_opened method), 688  
`is_opened()` (pylablib.devices.LighthousePhotonics.base.SproutG.is\_opened method), 691  
`is_opened()` (pylablib.devices.Lumel.base.LumelRE72Controller.is\_opened method), 693  
`is_opened()` (pylablib.devices.M2.base.ICEBlocDevice.is\_opened method), 696  
`is_opened()` (pylablib.devices.M2.emm.EMM.is\_opened method), 700  
`is_opened()` (pylablib.devices.M2.solstis.Solstis.is\_opened method), 706  
`is_opened()` (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera.is\_opened method), 708  
`is_opened()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice.is\_opened method), 717  
`is_opened()` (pylablib.devices.Newport.picomotor.Picomotor8742.is\_opened method), 739  
`is_opened()` (pylablib.devices.NI.daq.NIDAQ.is\_opened method), 718

- `is_opened()` (pylablib.devices.NKT.interbus.GenericInterbusDevice module), 727
- `is_opened()` (pylablib.devices.NKT.interbus.GenericInterbusDevice module), 729
- `is_opened()` (pylablib.devices.NKT.interbus.IInterbusModule module), 728
- `is_opened()` (pylablib.devices.NKT.interbus.InterbusSystem module), 734
- `is_opened()` (pylablib.devices.NKT.interbus.SuperKExtreme module), 730
- `is_opened()` (pylablib.devices.NKT.interbus.SuperKFront module), 731
- `is_opened()` (pylablib.devices.NKT.interbus.SuperKSelect module), 732
- `is_opened()` (pylablib.devices.NKT.interbus.SuperKSelect module), 733
- `is_opened()` (pylablib.devices.Omron.base.OmronE5xCam module), 748
- `is_opened()` (pylablib.devices.Ophir.base.OphirDevice module), 750
- `is_opened()` (pylablib.devices.Ophir.base.VegaPowerMeter module), 753
- `is_opened()` (pylablib.devices.OZOptics.base.DD100 module), 744
- `is_opened()` (pylablib.devices.OZOptics.base.EPC04 module), 746
- `is_opened()` (pylablib.devices.OZOptics.base.OZOpticsDevice module), 741
- `is_opened()` (pylablib.devices.OZOptics.base.TF100 module), 742
- `is_opened()` (pylablib.devices.PCO.SC2.PCOSC2Camera module), 755
- `is_opened()` (pylablib.devices.Pfeiffer.base.DPG202 module), 768
- `is_opened()` (pylablib.devices.Pfeiffer.base.TPG260 module), 766
- `is_opened()` (pylablib.devices.Photometrics.pvcam.Pvcam module), 772
- `is_opened()` (pylablib.devices.PhotonFocus.PhotonFocus.Shot module), 786
- `is_opened()` (pylablib.devices.PhotonFocus.PhotonFocus.Shot module), 810
- `is_opened()` (pylablib.devices.PhotonFocus.PhotonFocus.Shot module), 793
- `is_opened()` (pylablib.devices.PhotonFocus.PhotonFocus.Shot module), 802
- `is_opened()` (pylablib.devices.PhysikInstrumente.base.GenericModule module), 815
- `is_opened()` (pylablib.devices.PhysikInstrumente.base.PIE5 module), 821
- `is_opened()` (pylablib.devices.PhysikInstrumente.base.PIE5 module), 818
- `is_opened()` (pylablib.devices.PrincetonInstruments.picam module), 828
- `is_opened()` (pylablib.devices.Rigol.power\_supply.DP1116A module), 836
- `is_opened()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera module), 852
- `is_opened()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber module), 841
- `is_opened()` (pylablib.devices.Sirah.Matisse.SirahMatisse module), 861
- `is_opened()` (pylablib.devices.SmarAct.MCS2.MCS2 module), 869
- `is_opened()` (pylablib.devices.SmarAct.scu3d.SCU3D module), 874
- `is_opened()` (pylablib.devices.Standa.base.Standa8SMC module), 880
- `is_opened()` (pylablib.devices.Tektronix.base.DPO2000 module), 898
- `is_opened()` (pylablib.devices.Tektronix.base.ITektronixScope module), 886
- `is_opened()` (pylablib.devices.Tektronix.base.TDS2000 module), 891
- `is_opened()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor module), 915
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice module), 918
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.KinesisDevice module), 923
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor module), 933
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController module), 940
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor module), 937
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector module), 944
- `is_opened()` (pylablib.devices.Thorlabs.kinesis.MFF module), 926
- `is_opened()` (pylablib.devices.Thorlabs.misc.GenericPM module), 948
- `is_opened()` (pylablib.devices.Thorlabs.misc.PM160 module), 952
- `is_opened()` (pylablib.devices.Thorlabs.serial.FW module), 959
- `is_opened()` (pylablib.devices.Thorlabs.serial.FWv1 module), 962
- `is_opened()` (pylablib.devices.Thorlabs.serial.MDT69xA module), 966
- `is_opened()` (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface module), 955
- `is_opened()` (pylablib.devices.Thorlabs.TLCArea.ThorlabsTLCArea module), 904
- `is_opened()` (pylablib.devices.Toptica.ibeam.TopticaIBeam module), 970
- `is_opened()` (pylablib.devices.Trinamic.base.TMCM1110 module), 976

---

`is_opened()` (*pylablib.devices.Trinamic.base.TMCMx110 method*), 978  
`is_opened()` (*pylablib.devices.uc480.uc480.UC480Camera method*), 1025  
`is_opened()` (*pylablib.devices.Voltcraft.multimeter.VC705 method*), 982  
`is_opened()` (*pylablib.devices.Voltcraft.multimeter.VC880 method*), 986  
`is_opened()` (*pylablib.devices.Windows.joystick.Joystick method*), 988  
`is_ordered()` (in module *pylablib.core.dataproc.utils*), 162  
`is_output_enabled()` (*pylablib.devices.AWG.generic.GenericAWG method*), 456  
`is_output_enabled()` (*pylablib.devices.AWG.specific.Agilent33220A method*), 470  
`is_output_enabled()` (*pylablib.devices.AWG.specific.Agilent33500 method*), 464  
`is_output_enabled()` (*pylablib.devices.AWG.specific.InstekAFG2000 method*), 483  
`is_output_enabled()` (*pylablib.devices.AWG.specific.InstekAFG2225 method*), 477  
`is_output_enabled()` (*pylablib.devices.AWG.specific.RigolDG1000 method*), 501  
`is_output_enabled()` (*pylablib.devices.AWG.specific.RSInstekAFG21000 method*), 489  
`is_output_enabled()` (*pylablib.devices.AWG.specific.TektronixAFG1000 method*), 495  
`is_output_enabled()` (*pylablib.devices.ElektroAutomatik.base.PS2000B method*), 624  
`is_output_enabled()` (*pylablib.devices.Rigol.power\_supply.DP1116A method*), 834  
`is_ovp_enabled()` (*pylablib.devices.Rigol.power\_supply.DP1116A method*), 835  
`is_path_valid()` (in module *pylablib.core.utils.files*), 413  
`is_peer_closed()` (*pylablib.core.utils.ipc.SharedMemIPCTable method*), 437  
`is_peer_connected()` (*pylablib.core.utils.ipc.SharedMemIPCTable method*), 437  
`is_pixel_correction_enabled()` (*pylablib.devices.PCO.SC2.PCOSC2Camera method*), 758  
`is_pulse_output_running()` (*pylablib.devices.NI.daq.NIDAQ method*), 725  
`is_range()` (in module *pylablib.core.utils.indexing*), 433  
`is_remote_enabled()` (*pylablib.devices.ElektroAutomatik.base.PS2000B method*), 623  
`is_running()` (*pylablib.core.gui.widgets.container.IQContainer method*), 237  
`is_running()` (*pylablib.core.gui.widgets.container.IQWidgetContainer method*), 244  
`is_running()` (*pylablib.core.gui.widgets.container.QContainer method*), 240  
`is_running()` (*pylablib.core.gui.widgets.container.QDialogContainer method*), 258  
`is_running()` (*pylablib.core.gui.widgets.container.QFrameContainer method*), 253  
`is_running()` (*pylablib.core.gui.widgets.container.QGroupBoxContainer method*), 262  
`is_running()` (*pylablib.core.gui.widgets.container.QScrollAreaContainer method*), 270  
`is_running()` (*pylablib.core.gui.widgets.container.QScrollAreaContainer method*), 267  
`is_running()` (*pylablib.core.gui.widgets.container.QTabContainer method*), 273  
`is_running()` (*pylablib.core.gui.widgets.container.QWidgetContainer method*), 248  
`is_running()` (*pylablib.core.gui.widgets.param\_table.ParamTable method*), 294  
`is_running()` (*pylablib.core.gui.widgets.param\_table.StatusTable method*), 304  
`is_running()` (*pylablib.devices.BitFlow.BitFlow.BitFlowCamera.BufferM method*), 591  
`is_running()` (*pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.B method*), 587  
`is_running()` (*pylablib.devices.NI.daq.NIDAQ method*), 720  
`is_running()` (*pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusB method*), 806  
`is_sequence()` (in module *pylablib.core.utils.funcargparse*), 419  
`is_servo_enabled()` (*pylablib.devices.PhysikInstrumente.base.PIE515 method*), 820  
`is_servo_enabled()` (*pylablib.devices.PhysikInstrumente.base.PIE516 method*), 816  
`is_shutter_mode_possible()` (*pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method*), 547  
`is_shutter_opened()` (*pylablib.devices.LaserQuantum.base.Finesse*





is\_timer\_running() (py-lablib.core.gui.widgets.container.QTabContainer method), 273  
 is\_timer\_running() (py-lablib.core.gui.widgets.container.QWidgetContainer method), 249  
 is\_timer\_running() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 294  
 is\_timer\_running() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 304  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.generic.GenericAWG method), 458  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.Agilent33220A method), 471  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.Agilent33500 method), 464  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.InstekAFG2000 method), 483  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.InstekAFG2225 method), 477  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.RigolDG1000 method), 501  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 489  
 is\_trigger\_output\_enabled() (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 495  
 is\_unprintable\_character() (in module py-lablib.core.fileio.loadfile\_utils), 216  
 is\_velocity\_control\_enabled() (py-lablib.devices.PhysikInstrumente.base.PIE516 method), 816  
 is\_wait\_done() (pylablib.devices.interface.camera.FrameCounter method), 994  
 is\_wavelength\_control\_present() (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546  
 is\_wavemeter\_connected() (py-lablib.devices.M2.solstis.Solstis method), 701  
 is\_wavemeter\_lock\_on() (py-lablib.devices.M2.solstis.Solstis method), 702  
 ISingleValueHandling (class in py-lablib.core.gui.value\_handling), 316  
 ISkipableNotifier (class in py-lablib.core.thread.notifier), 366  
 ispan() (pylablib.core.dataproc.image.ROI method), 148  
 IStage (class in pylablib.devices.interface.stage), 1020  
 ITableDictionaryEntry (class in py-lablib.core.fileio.dict\_entry), 205  
 ITektronixScope (class in py-lablib.devices.Tektronix.base), 881  
 ItemAccessor (class in pylablib.core.utils.dictionary), 411  
 items() (pylablib.core.utils.dictionary.Dictionary method), 379  
 items() (pylablib.core.utils.dictionary.DictionaryPointer method), 390  
 items() (pylablib.core.utils.dictionary.FilterTree method), 407  
 items() (pylablib.core.utils.dictionary.PrefixTree method), 399  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 244  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.QDialogContainer method), 258  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.QFrameContainer method), 253  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 263  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 267  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.container.QWidgetContainer method), 249  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 280  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 283  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 294  
 iter\_sublayout\_items() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 304  
 iterbuttons() (pylablib.core.gui.widgets.button\_selector.ButtonSelector method), 233  
 iteritems() (pylablib.core.utils.dictionary.Dictionary method), 379  
 iteritems() (pylablib.core.utils.dictionary.DictionaryPointer method), 379

- method), 390
- iteritems() (pylablib.core.utils.dictionary.FilterTree method), 407
- iteritems() (pylablib.core.utils.dictionary.PrefixTree method), 399
- iterkeys() (pylablib.core.utils.dictionary.Dictionary method), 380
- iterkeys() (pylablib.core.utils.dictionary.DictionaryPointer method), 390
- iterkeys() (pylablib.core.utils.dictionary.FilterTree method), 407
- iterkeys() (pylablib.core.utils.dictionary.PrefixTree method), 399
- internodes() (pylablib.core.utils.dictionary.Dictionary method), 381
- internodes() (pylablib.core.utils.dictionary.DictionaryPointer method), 390
- internodes() (pylablib.core.utils.dictionary.FilterTree method), 407
- internodes() (pylablib.core.utils.dictionary.PrefixTree method), 399
- intervalues() (pylablib.core.utils.dictionary.Dictionary method), 380
- intervalues() (pylablib.core.utils.dictionary.DictionaryPointer method), 391
- intervalues() (pylablib.core.utils.dictionary.FilterTree method), 408
- intervalues() (pylablib.core.utils.dictionary.PrefixTree method), 400
- ITextInputFileFormat (class in pylablib.core.fileio.loadfile), 210
- ITextOutputFileFormat (class in pylablib.core.fileio.savefile), 224
- ITR90 (class in pylablib.devices.Leybold.base), 687
- IValueHandler (class in pylablib.core.gui.value\_handling), 311
- ivalues (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute), 535
- ivalues (pylablib.devices.Basler.pylon.BaslerPylonAttribute), 577
- ivalues (pylablib.devices.DCAM.DCAM.DCAMAttribute), 614
- ivalues (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute), 650
- ivalues (pylablib.devices.Photometrics.pvcam.PvcamAttribute), 770
- ivalues (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute), 781
- ivalues (pylablib.devices.PrincetonInstruments.picam.PicamAttribute), 827
- ivalues (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute), 840
- ivpwr (pylablib.devices.Standa.base.TFullState attribute), 877
- ivusb (pylablib.devices.Standa.base.TFullState attribute), 877
- ## J
- job (pylablib.core.thread.controller.QTaskThread.TBatchJob attribute), 351
- jog() (pylablib.devices.Arcus.performax.Performax2EXStage method), 559
- jog() (pylablib.devices.Arcus.performax.Performax4EXStage method), 554
- jog() (pylablib.devices.Arcus.performax.PerformaxDMXJSAStage method), 561
- jog() (pylablib.devices.Attocube.anc300.ANC300 method), 568
- jog() (pylablib.devices.Attocube.anc350.ANC350 method), 572
- jog() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 738
- jog() (pylablib.devices.Standa.base.Standa8SMC method), 879
- jog() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 930
- jog() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935
- jog() (pylablib.devices.Trinamic.base.TMCM1110 method), 973
- jog() (pylablib.devices.Trinamic.base.TMCMx110 method), 978
- jog1 (pylablib.devices.Thorlabs.kinesis.TPolCtlParams attribute), 919
- jog2 (pylablib.devices.Thorlabs.kinesis.TPolCtlParams attribute), 919
- jog3 (pylablib.devices.Thorlabs.kinesis.TPolCtlParams attribute), 919
- JoinedCallable (class in pylablib.core.dataproc.callable), 131
- JoinedCallable.NamesBoundCall (class in pylablib.core.dataproc.callable), 131
- joystick (class in pylablib.devices.Windows.joystick), 987
- jspan() (pylablib.core.dataproc.image.ROI method), 148
- ## K
- keep (pylablib.core.gui.widgets.button\_selector.ButtonSelector attribute), 233
- keep (pylablib.core.gui.widgets.combo\_box.ComboBox attribute), 234
- Keithley2110 (class in pylablib.devices.Keithley.multimeter), 666
- kernel (pylablib.core.dataproc.feature.Peak attribute), 135
- keyPressEvent() (pylablib.core.gui.widgets.edit.NumEdit method),

- 275
- `keyPressEvent()` (pylablib.core.gui.widgets.edit.TextEdit method), 274
- `keys()` (pylablib.core.utils.dictionary.Dictionary method), 380
- `keys()` (pylablib.core.utils.dictionary.DictionaryPointer method), 391
- `keys()` (pylablib.core.utils.dictionary.FilterTree method), 408
- `keys()` (pylablib.core.utils.dictionary.PrefixTree method), 400
- `kind` (pylablib.core.utils.ipc.TShmemVarDesc attribute), 436
- `kind` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute), 534
- `kind` (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 575
- `kind` (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 613
- `kind` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649
- `kind` (pylablib.devices.interface.camera.TStatusLineDescription attribute), 1019
- `kind` (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770
- `kind` (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 780
- `kind` (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 825
- `kind` (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute), 840
- `kind` (pylablib.devices.Voltcraft.multimeter.TVC880Reading attribute), 985
- `kind` (pylablib.devices.Windows.joystick.TJoystickEvent attribute), 987
- `kind` (pylablib.devices.Windows.joystick.TJoystickEventEx attribute), 987
- `KinesisDevice` (class in pylablib.devices.Thorlabs.kinesis), 921
- `KinesisMotor` (class in pylablib.devices.Thorlabs.kinesis), 927
- `KinesisPiezoController` (class in pylablib.devices.Thorlabs.kinesis), 938
- `KinesisPiezoMotor` (class in pylablib.devices.Thorlabs.kinesis), 934
- `KinesisQuadDetector` (class in pylablib.devices.Thorlabs.kinesis), 942
- `kinetic_cycle_time` (pylablib.devices.Andor.AndorSDK2.TCycleTimings attribute), 523
- `KJL3000` (class in pylablib.devices.KJL.base), 663
- `KJLBackendError`, 663
- `KJLError`, 663
- ## L
- `label` (pylablib.core.gui.widgets.param\_table.ParamTable.ParamRow attribute), 285
- `label` (pylablib.core.utils.string.TConversionClass attribute), 451
- `LabelIndicatorHandler` (class in pylablib.core.gui.value\_handling), 325
- `labels` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute), 535
- `labels` (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 577
- `labels` (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614
- `labels` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 650
- `labels` (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770
- `labels` (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 781
- `labels` (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 827
- `labels` (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute), 840
- `LabelValueHandler` (class in pylablib.core.gui.value\_handling), 318
- `Lakeshore218` (class in pylablib.devices.Lakeshore.base), 672
- `Lakeshore370` (class in pylablib.devices.Lakeshore.base), 677
- `LakeshoreBackendError`, 671
- `LakeshoreError`, 671
- `laser` (pylablib.devices.LighthousePhotonics.base.TWorkHours attribute), 690
- `laser_enabled` (pylablib.devices.LaserQuantum.base.TWorkHours attribute), 682
- `laser_on` (pylablib.devices.Toptica.ibeam.TWorkHours attribute), 968
- `laser_threshold` (pylablib.devices.LaserQuantum.base.TWorkHours attribute), 682
- `LaserQuantumBackendError`, 682
- `LaserQuantumError`, 682
- `latching_trigger()` (in module pylablib.core.dataproc.feature), 136
- `layout` (pylablib.core.gui.utils.TWidgetLocation attribute), 309
- `left` (pylablib.devices.interface.camera.TFramePosition attribute), 989
- `left_enable` (pylablib.devices.Trinamic.base.TLimitSwitchParams attribute), 971
- `level` (pylablib.devices.Tektronix.base.TTriggerParameters attribute), 881
- `LeyboldBackendError`, 685
- `LeyboldError`, 685

LibraryController (class in <i>pylablib.devices.Andor.AndorSDK2</i> ), 522	py- <i>list_applets()</i> (in module <i>pylablib.devices.SiliconSoftware.fgrab</i> ), 839
LibraryController (class in <i>pylablib.devices.Andor.AndorSDK3</i> ), 534	py- <i>list_backend_resources()</i> (in module <i>pylablib.core.devio.comm_backend</i> ), 192
LibraryController (class in <i>pylablib.devices.Andor.Shamrock</i> ), 544	py- <i>list_boards()</i> (in module <i>pylablib.devices.SiliconSoftware.fgrab</i> ), 838
LibraryController (class in <i>pylablib.devices.Basler.pylon</i> ), 574	py- <i>list_boards()</i> ( <i>pylablib.devices.Agilent.pressure.XGS600</i> method), 506
LibraryController (class in <i>pylablib.devices.DCAM.DCAM</i> ), 613	py- <i>list_cameras()</i> (in module <i>pylablib.devices.Basler.pylon</i> ), 575
LibraryController (class in <i>pylablib.devices.Mightex.MightexSSeries</i> ), 707	py- <i>list_cameras()</i> (in module <i>pylablib.devices.BitFlow.BitFlow</i> ), 585
LibraryController (class in <i>pylablib.devices.Photometrics.pvcam</i> ), 769	py- <i>list_cameras()</i> (in module <i>pylablib.devices.IMAQ.IMAQ</i> ), 633
LibraryController (class in <i>pylablib.devices.PhotonFocus.PhotonFocus</i> ), 779	py- <i>list_cameras()</i> (in module <i>pylablib.devices.IMAQdx.IMAQdx</i> ), 649
LibraryController (class in <i>pylablib.devices.PrincetonInstruments.picam</i> ), 824	py- <i>list_cameras()</i> (in module <i>pylablib.devices.Mightex.MightexSSeries</i> ), 708
LibraryController (class in <i>pylablib.devices.SmarAct.MCS2</i> ), 868	py- <i>list_cameras()</i> (in module <i>pylablib.devices.PCO.SC2</i> ), 754
LibraryController (class in <i>pylablib.devices.SmarAct.scu3d</i> ), 873	py- <i>list_cameras()</i> (in module <i>pylablib.devices.Photometrics.pvcam</i> ), 769
LibraryController (class in <i>pylablib.devices.Thorlabs.TLCamera</i> ), 902	py- <i>list_cameras()</i> (in module <i>pylablib.devices.PhotonFocus.PhotonFocus</i> ), 780
LibraryController (class in <i>pylablib.devices.utils.load_lib</i> ), 1033	py- <i>list_cameras()</i> (in module <i>pylablib.devices.PrincetonInstruments.picam</i> ), 824
LighthousePhotonicsBackendError, 689	<i>list_cameras()</i> (in module <i>pylablib.devices.Thorlabs.TLCamera</i> ), 902
LighthousePhotonicsError, 689	py- <i>list_cameras()</i> (in module <i>pylablib.devices.uc480.uc480</i> ), 1023
limit ( <i>pylablib.devices.Lakeshore.base.TLakeshore218CurvHead</i> attribute), 672	<i>list_devices()</i> (in module <i>pylablib.core.devio.hid</i> ), 194
limit() ( <i>pylablib.core.dataproc.image.ROI</i> method), 148	py- <i>list_devices()</i> (in module <i>pylablib.devices.NI.daq</i> ), 718
limit_errors_enabled() ( <i>pylablib.devices.Arcus.performax.Performax2EXStage</i> method), 559	py- <i>list_devices()</i> (in module <i>pylablib.devices.SmarAct.MCS2</i> ), 868
limit_errors_enabled() ( <i>pylablib.devices.Arcus.performax.Performax4EXStage</i> method), 553	py- <i>list_devices()</i> (in module <i>pylablib.devices.SmarAct.scu3d</i> ), 874
limit_switch ( <i>pylablib.devices.Thorlabs.kinesis.THomePilot</i> attribute), 919	py- <i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice</i> static method), 916
limit_to_range() (in module <i>pylablib.core.utils.numerical</i> ), 444	py- <i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.KinesisDevice</i> static method), 923
LimitError, 308	<i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.KinesisMotor</i> static method), 933
linear_to_sRGB() (in module <i>pylablib.devices.utils.color</i> ), 1031	<i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.KinesisPiezoController</i> static method), 940
LinearTransform (class in <i>pylablib.core.dataproc.transform</i> ), 161	<i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</i> static method), 937
LineEditValueHandler (class in <i>pylablib.core.gui.value_handling</i> ), 317	<i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector</i> static method), 944
lines ( <i>pylablib.devices.Andor.Shamrock.TGratingInfo</i> attribute), 545	<i>list_devices()</i> ( <i>pylablib.devices.Thorlabs.kinesis.MFF</i> static method), 944



- static method*), 926
- `list_dir()` (in module `pylablib.core.utils.files`), 415
- `list_dir_recursive()` (in module `pylablib.core.utils.files`), 416
- `list_joysticks()` (in module `pylablib.devices.Windows.joystick`), 987
- `list_kinesis_devices()` (in module `pylablib.devices.Thorlabs.kinesis`), 916
- `list_opened_files()` (`pylablib.core.fileio.location.FolderFileSystemDataLocation` *method*), 222
- `list_opened_files()` (`pylablib.core.fileio.location.IDataLocation` *method*), 219
- `list_opened_files()` (`pylablib.core.fileio.location.IFileSystemDataLocation` *method*), 219
- `list_opened_files()` (`pylablib.core.fileio.location.OpenedFileLocation` *method*), 219
- `list_opened_files()` (`pylablib.core.fileio.location.PrefixedFileSystemDataLocation` *method*), 221
- `list_opened_files()` (`pylablib.core.fileio.location.SingleFileSystemDataLocation` *method*), 220
- `list_resources()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` *static method*), 180
- `list_resources()` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` *static method*), 188
- `list_resources()` (`pylablib.core.devio.comm_backend.IDeviceCommBackend` *static method*), 172
- `list_resources()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` *static method*), 183
- `list_resources()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` *static method*), 185
- `list_resources()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` *static method*), 190
- `list_resources()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` *static method*), 177
- `list_resources()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` *static method*), 173
- `list_spectrographs()` (in module `pylablib.devices.Andor.Shamrock`), 544
- `list_usb_performax_devices()` (in module `pylablib.devices.Arcus.performax`), 551
- `listen()` (in module `pylablib.core.utils.net`), 443
- `ListIndex` (class in `pylablib.core.utils.indexing`), 434
- `ListIndexNoSlice` (class in `pylablib.core.utils.indexing`), 434
- `LM500` (class in `pylablib.devices.Cryomagnetics.base`), 604
- `LM510` (class in `pylablib.devices.Cryomagnetics.base`), 608
- `load()` (in module `pylablib.core.utils.strdump`), 449
- `load()` (`pylablib.core.utils.strdump.StrDumper` *method*), 448
- `load()` (`pylablib.devices.BitFlow.BitFlow.CameraFileEditor` *method*), 596
- `load_bin()` (in module `pylablib.core.fileio.loadfile`), 213
- `load_bin_desc()` (in module `pylablib.core.fileio.loadfile`), 214
- `load_csv()` (in module `pylablib.core.fileio.loadfile`), 213
- `load_csv_desc()` (in module `pylablib.core.fileio.loadfile`), 213
- `load_dict()` (in module `pylablib.core.fileio.loadfile`), 214
- `load_dict_file()` (`pylablib.core.fileio.dict_entry.ExternalNumpyDictionaryEntry` *class method*), 209
- `load_file()` (`pylablib.core.fileio.dict_entry.IExternalFileDictionaryEntry` *class method*), 209
- `load_generic()` (in module `pylablib.core.fileio.loadfile`), 215
- `load_lib()` (in module `pylablib.devices.utils.load_lib`), 1032
- `load_logfile()` (in module `pylablib.core.devio.backend_logger`), 169
- `load_par()` (in module `pylablib`), 1034
- `loads()` (in module `pylablib.core.utils.strdump`), 449
- `loads()` (`pylablib.core.utils.strdump.StrDumper` *method*), 448
- `loc` (`pylablib.core.fileio.location.LocationFile` *attribute*), 218
- `LocationFile` (class in `pylablib.core.fileio.location`), 218
- `LocationName` (class in `pylablib.core.fileio.location`), 217
- `lock()` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` *method*), 180
- `lock()` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` *method*), 188
- `lock()` (`pylablib.core.devio.comm_backend.ICommBackendWrapper` *method*), 193
- `lock()` (`pylablib.core.devio.comm_backend.IDeviceCommBackend` *method*), 171
- `lock()` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` *method*), 183
- `lock()` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` *method*), 185
- `lock()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` *method*), 185

- method*), 191
- `lock()` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` *method*), 177
- `lock()` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` *method*), 173
- `lock()` (`pylablib.core.devio.SCP1.SCPIDevice` *method*), 168
- `lock()` (`pylablib.devices.Agilent.pressure.XGS600` *method*), 507
- `lock()` (`pylablib.devices.Arduino.base.IArduinoDevice` *method*), 565
- `lock()` (`pylablib.devices.Attocube.anc300.ANC300` *method*), 569
- `lock()` (`pylablib.devices.Attocube.anc350.ANC350` *method*), 573
- `lock()` (`pylablib.devices.AWG.generic.GenericAWG` *method*), 459
- `lock()` (`pylablib.devices.AWG.specific.Agilent33220A` *method*), 471
- `lock()` (`pylablib.devices.AWG.specific.Agilent33500` *method*), 465
- `lock()` (`pylablib.devices.AWG.specific.InstekAFG2000` *method*), 483
- `lock()` (`pylablib.devices.AWG.specific.InstekAFG2225` *method*), 477
- `lock()` (`pylablib.devices.AWG.specific.RigolDG1000` *method*), 501
- `lock()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` *method*), 489
- `lock()` (`pylablib.devices.AWG.specific.TektronixAFG1000` *method*), 495
- `lock()` (`pylablib.devices.Conrad.base.RelayBoard` *method*), 599
- `lock()` (`pylablib.devices.Cryocon.base.Cryocon1x` *method*), 601
- `lock()` (`pylablib.devices.Cryomagnetics.base.LM500` *method*), 606
- `lock()` (`pylablib.devices.Cryomagnetics.base.LM510` *method*), 610
- `lock()` (`pylablib.devices.ElektroAutomatik.base.PS2000B` *method*), 625
- `lock()` (`pylablib.devices.Hubner.Cobolt.Cobolt` *method*), 632
- `lock()` (`pylablib.devices.Keithley.multimeter.Keithley2110` *method*), 669
- `lock()` (`pylablib.devices.KJL.base.KJL300` *method*), 665
- `lock()` (`pylablib.devices.Lakeshore.base.Lakeshore218` *method*), 675
- `lock()` (`pylablib.devices.Lakeshore.base.Lakeshore370` *method*), 680
- `lock()` (`pylablib.devices.LaserQuantum.base.Finesse` *method*), 684
- `lock()` (`pylablib.devices.Leybold.base.GenericITR` *method*), 687
- `lock()` (`pylablib.devices.Leybold.base.ITR90` *method*), 688
- `lock()` (`pylablib.devices.LighthousePhotonics.base.SproutG` *method*), 691
- `lock()` (`pylablib.devices.Lumel.base.LumelRE72Controller` *method*), 694
- `lock()` (`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` *method*), 717
- `lock()` (`pylablib.devices.Newport.picomotor.Picomotor8742` *method*), 739
- `lock()` (`pylablib.devices.NKT.interbus.GenericInterbusDevice` *method*), 727
- `lock()` (`pylablib.devices.NKT.interbus.InterbusSystem` *method*), 734
- `lock()` (`pylablib.devices.Omron.base.OmronE5xCController` *method*), 748
- `lock()` (`pylablib.devices.Ophir.base.OphirDevice` *method*), 750
- `lock()` (`pylablib.devices.Ophir.base.VegaPowerMeter` *method*), 754
- `lock()` (`pylablib.devices.OZOptics.base.DD100` *method*), 744
- `lock()` (`pylablib.devices.OZOptics.base.EPC04` *method*), 746
- `lock()` (`pylablib.devices.OZOptics.base.OZOpticsDevice` *method*), 741
- `lock()` (`pylablib.devices.OZOptics.base.TF100` *method*), 742
- `lock()` (`pylablib.devices.Pfeiffer.base.DPG202` *method*), 768
- `lock()` (`pylablib.devices.Pfeiffer.base.TPG260` *method*), 767
- `lock()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` *method*), 816
- `lock()` (`pylablib.devices.PhysikInstrumente.base.PIE515` *method*), 822
- `lock()` (`pylablib.devices.PhysikInstrumente.base.PIE516` *method*), 818
- `lock()` (`pylablib.devices.Rigol.power_supply.DP1116A` *method*), 836
- `lock()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` *method*), 862
- `lock()` (`pylablib.devices.Standa.base.Standa8SMC` *method*), 880
- `lock()` (`pylablib.devices.Tektronix.base.DPO2000` *method*), 898
- `lock()` (`pylablib.devices.Tektronix.base.ITektronixScope` *method*), 886
- `lock()` (`pylablib.devices.Tektronix.base.TDS2000` *method*), 891
- `lock()` (`pylablib.devices.Thorlabs.elliptec.ElliptecMotor` *method*), 915
- `lock()` (`pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice` *method*), 918

- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisDevice* method), 191
- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisMotor* method), 923
- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoController* method), 933
- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor* method), 940
- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor* method), 937
- `lock()` (*pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector* method), 944
- `lock()` (*pylablib.devices.Thorlabs.kinesis.MFF* method), 926
- `lock()` (*pylablib.devices.Thorlabs.misc.GenericPM* method), 948
- `lock()` (*pylablib.devices.Thorlabs.misc.PM160* method), 952
- `lock()` (*pylablib.devices.Thorlabs.serial.FW* method), 959
- `lock()` (*pylablib.devices.Thorlabs.serial.FWv1* method), 962
- `lock()` (*pylablib.devices.Thorlabs.serial.MDT69xA* method), 966
- `lock()` (*pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface* method), 955
- `lock()` (*pylablib.devices.Toptica.ibeam.TopticaIBeam* method), 970
- `lock()` (*pylablib.devices.Trinamic.base.TMCM1110* method), 976
- `lock()` (*pylablib.devices.Trinamic.base.TMCMx110* method), 978
- `lock()` (*pylablib.devices.Voltcraft.multimeter.VC7055* method), 982
- `lock()` (*pylablib.devices.Voltcraft.multimeter.VC880* method), 986
- `lock_etalon()` (*pylablib.devices.M2.solstis.Solstis* method), 702
- `lock_reference_cavity()` (*pylablib.devices.M2.solstis.Solstis* method), 703
- `lock_wavemeter()` (*pylablib.devices.M2.solstis.Solstis* method), 701
- `locking()` (*pylablib.core.devio.comm\_backend.FT232DevioBackend* method), 180
- `locking()` (*pylablib.core.devio.comm\_backend.HIDDeviceBackend* method), 188
- `locking()` (*pylablib.core.devio.comm\_backend.ICommBackend* method), 193
- `locking()` (*pylablib.core.devio.comm\_backend.IDeviceCommunicationBackend* method), 171
- `locking()` (*pylablib.core.devio.comm\_backend.NetworkDeviceBackend* method), 183
- `locking()` (*pylablib.core.devio.comm\_backend.PyUSBDeviceBackend* method), 186
- `locking()` (*pylablib.core.devio.comm\_backend.RecordedDeviceBackend* method), 191
- `locking()` (*pylablib.core.devio.comm\_backend.SerialDeviceBackend* method), 177
- `locking()` (*pylablib.core.devio.comm\_backend.VisaDeviceBackend* method), 174
- `locking()` (*pylablib.core.devio.SCPISCPIDevice* method), 168
- `locking()` (*pylablib.devices.Agilent.pressure.XGS600* method), 507
- `locking()` (*pylablib.devices.Arduino.base.IArduinoDevice* method), 565
- `locking()` (*pylablib.devices.Attocube.anc300.ANC300* method), 569
- `locking()` (*pylablib.devices.Attocube.anc350.ANC350* method), 573
- `locking()` (*pylablib.devices.AWG.generic.GenericAWG* method), 459
- `locking()` (*pylablib.devices.AWG.specific.Agilent33220A* method), 471
- `locking()` (*pylablib.devices.AWG.specific.Agilent33500* method), 465
- `locking()` (*pylablib.devices.AWG.specific.InstekAFG2000* method), 483
- `locking()` (*pylablib.devices.AWG.specific.InstekAFG2225* method), 477
- `locking()` (*pylablib.devices.AWG.specific.RigolDG1000* method), 501
- `locking()` (*pylablib.devices.AWG.specific.RSInstekAFG21000* method), 489
- `locking()` (*pylablib.devices.AWG.specific.TektronixAFG1000* method), 495
- `locking()` (*pylablib.devices.Conrad.base.RelayBoard* method), 599
- `locking()` (*pylablib.devices.Cryocon.base.Cryocon1x* method), 601
- `locking()` (*pylablib.devices.Cryomagnetics.base.LM500* method), 606
- `locking()` (*pylablib.devices.Cryomagnetics.base.LM510* method), 610
- `locking()` (*pylablib.devices.ElektroAutomatik.base.PS2000B* method), 625
- `locking()` (*pylablib.devices.Hubner.Cobolt.Cobolt* method), 632
- `locking()` (*pylablib.devices.Keithley.multimeter.Keithley2110* method), 669
- `locking()` (*pylablib.devices.KJL.base.KJL300* method), 665
- `locking()` (*pylablib.devices.Lakeshore.base.Lakeshore218* method), 675
- `locking()` (*pylablib.devices.Lakeshore.base.Lakeshore370* method), 680
- `locking()` (*pylablib.devices.LaserQuantum.base.Finesse* method), 684
- `locking()` (*pylablib.devices.Leybold.base.GenericITR* method), 684

- method), 687
- locking() (pylablib.devices.Leybold.base.ITR90 method), 689
- locking() (pylablib.devices.LighthousePhotonics.base.Springle method), 691
- locking() (pylablib.devices.Lumel.base.LumelRE72Controller method), 694
- locking() (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 717
- locking() (pylablib.devices.Newport.picomotor.PicomotorBase method), 739
- locking() (pylablib.devices.NKT.interbus.GenericInterbusDevice method), 727
- locking() (pylablib.devices.NKT.interbus.InterbusSystem method), 735
- locking() (pylablib.devices.Omron.base.OmronE5xCController method), 748
- locking() (pylablib.devices.Ophir.base.OphirDevice method), 750
- locking() (pylablib.devices.Ophir.base.VegaPowerMeter method), 754
- locking() (pylablib.devices.OZOptics.base.DD100 method), 744
- locking() (pylablib.devices.OZOptics.base.EPC04 method), 746
- locking() (pylablib.devices.OZOptics.base.OZOpticsDevice method), 741
- locking() (pylablib.devices.OZOptics.base.TF100 method), 742
- locking() (pylablib.devices.Pfeiffer.base.DPG202 method), 768
- locking() (pylablib.devices.Pfeiffer.base.TPG260 method), 767
- locking() (pylablib.devices.PhysikInstrumente.base.GenericPI method), 816
- locking() (pylablib.devices.PhysikInstrumente.base.PIE5Base method), 822
- locking() (pylablib.devices.PhysikInstrumente.base.PIE5Base method), 818
- locking() (pylablib.devices.Rigol.power\_supply.DPI116A method), 836
- locking() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 862
- locking() (pylablib.devices.Standa.base.Standa8SMC method), 880
- locking() (pylablib.devices.Tektronix.base.DPO2000 method), 898
- locking() (pylablib.devices.Tektronix.base.ITektronixScope method), 886
- locking() (pylablib.devices.Tektronix.base.TDS2000 method), 891
- locking() (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 915
- locking() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 918
- locking() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 923
- locking() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 933
- locking() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 940
- locking() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 937
- locking() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 944
- locking() (pylablib.devices.Thorlabs.kinesis.MFF method), 926
- locking() (pylablib.devices.Thorlabs.misc.GenericPM method), 948
- locking() (pylablib.devices.Thorlabs.misc.PM160 method), 952
- locking() (pylablib.devices.Thorlabs.serial.FW method), 959
- locking() (pylablib.devices.Thorlabs.serial.FWv1 method), 962
- locking() (pylablib.devices.Thorlabs.serial.MDT69xA method), 966
- locking() (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 955
- locking() (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 970
- locking() (pylablib.devices.Trinamic.base.TMCM1110 method), 976
- locking() (pylablib.devices.Trinamic.base.TMCMx110 method), 978
- locking() (pylablib.devices.Voltcraft.multimeter.VC7055 method), 982
- locking() (pylablib.devices.Voltcraft.multimeter.VC880 method), 986
- lockpoint (pylablib.devices.Sirah.Matisse.TFastpiezoCtlParameters attribute), 856
- log() (pylablib.core.devio.backend\_logger.BackendLogger method), 169
- logerror() (in module pylablib.core.devio.comm\_backend), 170
- loop (pylablib.core.gui.widgets.container.TTimerEvent attribute), 235
- loop (pylablib.devices.Thorlabs.elliptec.TMotorInfo attribute), 912
- loop() (pylablib.devices.PCO.SC2.PCOSC2Camera.ScheduleLooper method), 756
- loop\_read() (pylablib.core.devio.hid.HIDDevice.Reader method), 195
- lorentzian\_k() (in module pylablib.core.dataproc.specfunc), 151
- low\_pass\_filter() (in module pylablib.core.dataproc.filters), 137
- Lowthresh (pylablib.devices.Pfeiffer.base.TTPG260SwitchSettings



[attribute](#)), 764  
[low\\_value](#) (pylablib.devices.Lakeshore.base.TLakeshore218AnalogSetting attribute), 672  
[low\\_value](#) (pylablib.devices.Lakeshore.base.TLakeshore370AnalogSetting attribute), 677  
[lower\\_limit](#) (pylablib.devices.Sirah.Matisse.TRefcellWaveformParameters attribute), 856  
[lower\\_limit](#) (pylablib.devices.Sirah.Matisse.TScanParameters attribute), 856  
[lowlevel\\_calibrate\(\)](#) (pylablib.devices.SmarAct.MCS2.MCS2 method), 872  
[lowlevel\\_move\(\)](#) (pylablib.devices.SmarAct.MCS2.MCS2 method), 872  
[lowlevel\\_reference\(\)](#) (pylablib.devices.SmarAct.MCS2.MCS2 method), 872  
[LumelRE72Controller](#) (class in pylablib.devices.Lumel.base), 692

## M

[m](#) (pylablib.core.thread.controller.QTaskThread attribute), 350  
[m](#) (pylablib.devices.NKT.interbus.InterbusSystem attribute), 733  
[M2CommunicationError](#), 695  
[M2Error](#), 695  
[M2ParseError](#), 695  
[main\\_board\\_rev](#) (pylablib.devices.Agilent.pressure.TXGS6000Device attribute), 505  
[make\\_comment\\_line\(\)](#) (pylablib.core.fileio.savefile.CSVTableOutputFileFormat method), 226  
[make\\_comment\\_line\(\)](#) (pylablib.core.fileio.savefile.DictionaryOutputFileFormat method), 227  
[make\\_comment\\_line\(\)](#) (pylablib.core.fileio.savefile.ITextOutputFileFormat method), 225  
[make\\_flat\\_namedtuple\(\)](#) (in module pylablib.core.utils.general), 425  
[make\\_prop\\_line\(\)](#) (pylablib.core.fileio.savefile.CSVTableOutputFileFormat method), 226  
[make\\_prop\\_line\(\)](#) (pylablib.core.fileio.savefile.DictionaryOutputFileFormat method), 227  
[make\\_prop\\_line\(\)](#) (pylablib.core.fileio.savefile.ITextOutputFileFormat method), 225  
[make\\_savetime\\_line\(\)](#) (pylablib.core.fileio.savefile.CSVTableOutputFileFormat method), 226  
[make\\_savetime\\_line\(\)](#) (pylablib.core.fileio.savefile.DictionaryOutputFileFormat method), 227  
[make\\_savetime\\_line\(\)](#) (pylablib.core.fileio.savefile.ITextOutputFileFormat method), 225  
[make\\_sequence\(\)](#) (in module pylablib.core.utils.funcargparse), 420  
[man\\_value](#) (pylablib.devices.Lakeshore.base.TLakeshore218AnalogSetting attribute), 672  
[man\\_value](#) (pylablib.devices.Lakeshore.base.TLakeshore370AnalogSetting attribute), 677  
[mandatory\\_args\\_num\(\)](#) (pylablib.core.utils.functions.FunctionSignature method), 421  
[manufacturer](#) (pylablib.core.devio.hid.TDeviceDescription attribute), 194  
[manufacturer](#) (pylablib.devices.ElektroAutomatik.base.TDeviceInfo attribute), 622  
[manufacturer](#) (pylablib.devices.PhotonFocus.PhotonFocus.TCameraInfo attribute), 780  
[manufacturer](#) (pylablib.devices.Thorlabs.misc.TPMDeviceInfo attribute), 945  
[manufacturer](#) (pylablib.devices.uc480.uc480.TDeviceInfo attribute), 1023  
[map\\_container\(\)](#) (in module pylablib.core.utils.general), 425  
[map\\_dict\\_keys\(\)](#) (in module pylablib.core.utils.general), 426  
[map\\_dict\\_values\(\)](#) (in module pylablib.core.utils.general), 426  
[map\\_self\(\)](#) (pylablib.core.utils.dictionary.Dictionary method), 383  
[map\\_self\(\)](#) (pylablib.core.utils.dictionary.DictionaryPointer method), 391  
[map\\_self\(\)](#) (pylablib.core.utils.dictionary.FilterTree method), 408  
[map\\_self\(\)](#) (pylablib.core.utils.dictionary.PrefixTree method), 400  
[mark\\_unscheduled\(\)](#) (pylablib.core.thread.controller.QTaskThread.Job method), 351  
[match\(\)](#) (pylablib.core.utils.dictionary.FilterTree method), 403  
[MatisseTuner](#) (class in pylablib.devices.Sirah.tuner), 864  
[max](#) (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute), 535  
[max](#) (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576  
[max](#) (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614  
[max](#) (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 650

max (pylablib.devices.interface.camera.TAxisROILimit attribute), 1010	lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715
max (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770	mb_read_discrete_inputs() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
max (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 781	mb_read_holding_registers() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
max (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 826	mb_read_holding_registers() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715
max (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute), 840	mb_read_holding_registers() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
max_args_num() (pylablib.core.utils.functions.FunctionSignature method), 421	mb_read_input_registers() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
max_step_frequency (py-lablib.devices.SmarAct.MCS2.TCLMoveParams attribute), 869	mb_read_input_registers() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715
max_velocity (pylablib.devices.Thorlabs.kinesis.TJogParams attribute), 919	mb_read_input_registers() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
max_velocity (pylablib.devices.Thorlabs.kinesis.TVelocityParam attribute), 919	mb_scan_devices() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
max_voltage (pylablib.devices.Thorlabs.kinesis.TPZMotorDriveParam attribute), 920	mb_scan_devices() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716
maxbin (pylablib.devices.interface.camera.TAxisROILimit attribute), 1010	mb_scan_devices() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
mb_get_default_address() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694	mb_scan_devices() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716
mb_get_default_address() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715	mb_scan_devices() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
mb_get_default_address() (py-lablib.devices.Omron.base.OmronE5xCController method), 748	mb_set_default_address() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
mb_get_device_id() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694	mb_set_default_address() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715
mb_get_device_id() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716	mb_set_default_address() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
mb_get_device_id() (py-lablib.devices.Omron.base.OmronE5xCController method), 748	mb_using_address() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
mb_read_coils() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694	mb_using_address() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715
mb_read_coils() (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 715	mb_using_address() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
mb_read_coils() (py-lablib.devices.Omron.base.OmronE5xCController method), 748	mb_write_multiple_coils() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694
mb_read_discrete_inputs() (py-lablib.devices.Lumel.base.LumelRE72Controller method), 694	mb_write_multiple_coils() (py-lablib.devices.Omron.base.OmronE5xCController method), 748
mb_read_discrete_inputs() (py-lablib.devices.Omron.base.OmronE5xCController method), 748	

`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` (pylablib.core.utils.functions.FunctionSignature method), 716  
`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` (pylablib.core.utils.functions.FunctionSignature static method), 421  
`mb_write_multiple_coils()` (pylablib.devices.Omron.base.OmronE5xCController method), 748  
`mb_write_multiple_coils()` (pylablib.devices.Omron.base.OmronE5xCController method), 426  
`mb_write_multiple_holding_registers()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 694  
`mb_write_multiple_holding_registers()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 917  
`mb_write_multiple_holding_registers()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 133  
`mb_write_multiple_holding_registers()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 133  
`mb_write_multiple_holding_registers()` (pylablib.devices.Omron.base.OmronE5xCController method), 748  
`mb_write_multiple_holding_registers()` (pylablib.devices.Omron.base.OmronE5xCController method), 423  
`mb_write_single_coil()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 694  
`mb_write_single_coil()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 423  
`mb_write_single_coil()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716  
`mb_write_single_coil()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 924  
`mb_write_single_coil()` (pylablib.devices.Omron.base.OmronE5xCController method), 748  
`mb_write_single_coil()` (pylablib.devices.Omron.base.OmronE5xCController method), 708  
`mb_write_single_coil()` (pylablib.devices.Omron.base.OmronE5xCController method), 709  
`mb_write_single_holding_register()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 694  
`mb_write_single_holding_register()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 1024  
`mb_write_single_holding_register()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 716  
`mb_write_single_holding_register()` (pylablib.devices.Modbus.modbus.GenericModbusRTUDevice method), 535  
`mb_write_single_holding_register()` (pylablib.devices.Omron.base.OmronE5xCController method), 748  
`mb_write_single_holding_register()` (pylablib.devices.Omron.base.OmronE5xCController method), 576  
`mb_write_single_holding_register()` (pylablib.devices.Omron.base.OmronE5xCController method), 614  
`MCS2` (class in `pylablib.devices.SmarAct.MCS2`), 869  
`MDT69xA` (class in `pylablib.devices.Thorlabs.serial`), 964  
`measure_capacitance()` (pylablib.devices.Attocube.anc300.ANC300 method), 567  
`measure_level()` (pylablib.devices.Cryomagnetics.base.LM500 method), 605  
`measure_level()` (pylablib.devices.Cryomagnetics.base.LM510 method), 610  
`median_filter()` (in module `pylablib.core.dataproc.filters`), 138  
`merge()` (in module `pylablib.core.dataproc.utils`), 163  
`merge()` (pylablib.core.utils.dictionary.Dictionary method), 381  
`merge()` (pylablib.core.utils.dictionary.DictionaryPointer method), 392  
`merge()` (pylablib.core.utils.dictionary.FilterTree method), 408  
`merge()` (pylablib.core.utils.dictionary.PrefixTree method), 400  
`merge_dicts()` (in module `pylablib.core.utils.general`), 426  
`messageID` (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice.CommD attribute), 917  
`messageID` (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice.CommD attribute), 917  
`MethodCallable` (class in `pylablib.core.dataproc.callable`), 133  
`MethodCallable.NamesBoundCall` (class in `pylablib.core.dataproc.callable`), 133  
`MethodObjectCall` (class in `pylablib.core.utils.functions`), 423  
`MethodObjectProperty` (class in `pylablib.core.utils.functions`), 423  
`MFF` (class in `pylablib.devices.Thorlabs.kinesis`), 924  
`MightexError`, 714  
`MightexSSeriesCamera` (class in `pylablib.devices.Mightex.MightexSSeries`), 708  
`MightexSSeriesCamera.ReceiveLooper` (class in `pylablib.devices.Mightex.MightexSSeries`), 709  
`MightexTimeoutError`, 714  
`millisecond` (pylablib.devices.uc480.uc480.TTimestamp attribute), 1024  
`min` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute), 535  
`min` (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576  
`min` (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614  
`min` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649  
`min` (pylablib.devices.interface.camera.TAxisROI.Limit attribute), 1010  
`min` (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770  
`min` (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 781  
`min` (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 826  
`min` (pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute), 840  
`min_run_time` (pylablib.core.thread.controller.QTaskThread.TBatchJob attribute), 351  
`min_velocity` (pylablib.devices.Thorlabs.kinesis.TJogParams attribute), 919  
`min_velocity` (pylablib.devices.Thorlabs.kinesis.TVelocityParams attribute), 919  
`minute` (pylablib.devices.uc480.uc480.TTimestamp attribute), 1024  
`MissingGUIHandlerError`, 326  
`mod_state` (pylablib.devices.Thorlabs.kinesis.TDeviceInfo attribute), 919

- [attribute](#)), 916
- [ModbusBackendError](#), 715
- [ModbusError](#), 714
- [mode](#) ([pylablib.devices.ElektroAutomatik.base.TStatus attribute](#)), 622
- [mode](#) ([pylablib.devices.Keithley.multimeter.TAveragingParameters attribute](#)), 666
- [mode](#) ([pylablib.devices.Lakeshore.base.TLakeshore218Analogs attribute](#)), 672
- [mode](#) ([pylablib.devices.Lakeshore.base.TLakeshore370Analogs attribute](#)), 677
- [mode](#) ([pylablib.devices.Ophir.base.TWavelengthInfo attribute](#)), 751
- [mode](#) ([pylablib.devices.Sirah.Matisse.TRefcellWaveformParameters attribute](#)), 856
- [mode](#) ([pylablib.devices.Sirah.Matisse.TScanParameters attribute](#)), 856
- [mode](#) ([pylablib.devices.Thorlabs.kinesis.TJogParams attribute](#)), 919
- [mode](#) ([pylablib.devices.Thorlabs.kinesis.TPZMotorJogParams attribute](#)), 921
- [mode](#) ([pylablib.devices.Trinamic.base.THomeParams attribute](#)), 972
- [model](#) ([pylablib.devices.Basler.pylon.TCameraInfo attribute](#)), 575
- [model](#) ([pylablib.devices.Basler.pylon.TDeviceInfo attribute](#)), 577
- [model](#) ([pylablib.devices.BitFlow.BitFlow.TDeviceInfo attribute](#)), 585
- [model](#) ([pylablib.devices.DCAM.DCAM.TDeviceInfo attribute](#)), 615
- [model](#) ([pylablib.devices.ElektroAutomatik.base.TDeviceInfo attribute](#)), 622
- [model](#) ([pylablib.devices.HighFinesse.wlm.TDeviceInfo attribute](#)), 625
- [model](#) ([pylablib.devices.Hubner.Cobolt.TDeviceInfo attribute](#)), 630
- [model](#) ([pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute](#)), 648
- [model](#) ([pylablib.devices.IMAQdx.IMAQdx.TDeviceInfo attribute](#)), 650
- [model](#) ([pylablib.devices.Lumel.base.TDeviceInfo attribute](#)), 692
- [model](#) ([pylablib.devices.Mightex.MightexSSeries.TCameraInfo attribute](#)), 707
- [model](#) ([pylablib.devices.Mightex.MightexSSeries.TDeviceInfo attribute](#)), 708
- [model](#) ([pylablib.devices.NI.daq.TDeviceInfo attribute](#)), 717
- [model](#) ([pylablib.devices.Omron.base.TDeviceInfo attribute](#)), 746
- [model](#) ([pylablib.devices.PCO.SC2.TDeviceInfo attribute](#)), 754
- [model](#) ([pylablib.devices.PhotonFocus.PhotonFocus.TDeviceInfo attribute](#)), 781
- [model](#) ([pylablib.devices.PrincetonInstruments.picam.TCameraInfo attribute](#)), 824
- [model](#) ([pylablib.devices.PrincetonInstruments.picam.TDeviceInfo attribute](#)), 827
- [model](#) ([pylablib.devices.Thorlabs.TLCamera.TDeviceInfo attribute](#)), 902
- [model](#) ([pylablib.devices.uc480.uc480.TCameraInfo attribute](#)), 1023
- [model](#) ([pylablib.devices.uc480.uc480.TDeviceInfo attribute](#)), 1023
- [model\\_no](#) ([pylablib.devices.Thorlabs.elliptec.TDeviceInfo attribute](#)), 911
- [models\\_no](#) ([pylablib.devices.Thorlabs.kinesis.TDeviceInfo attribute](#)), 916
- [module](#)
  - [pylablib](#), 1034
  - [pylablib.core](#), 455
  - [pylablib.core.dataproc](#), 165
  - [pylablib.core.dataproc.callable](#), 129
  - [pylablib.core.dataproc.ctransform\\_fallback](#), 134
  - [pylablib.core.dataproc.feature](#), 135
  - [pylablib.core.dataproc.filters](#), 137
  - [pylablib.core.dataproc.fitting](#), 141
  - [pylablib.core.dataproc.fourier](#), 144
  - [pylablib.core.dataproc.iir\\_transform](#), 147
  - [pylablib.core.dataproc.image](#), 147
  - [pylablib.core.dataproc.interpolate](#), 148
  - [pylablib.core.dataproc.specfunc](#), 151
  - [pylablib.core.dataproc.table\\_wrap](#), 152
  - [pylablib.core.dataproc.transform](#), 161
  - [pylablib.core.dataproc.utils](#), 162
  - [pylablib.core.devio](#), 202
  - [pylablib.core.devio.backend\\_logger](#), 169
  - [pylablib.core.devio.base](#), 170
  - [pylablib.core.devio.comm\\_backend](#), 170
  - [pylablib.core.devio.data\\_format](#), 193
  - [pylablib.core.devio.hid](#), 194
  - [pylablib.core.devio.hid\\_base](#), 196
  - [pylablib.core.devio.interface](#), 196
  - [pylablib.core.devio.SCPi](#), 165
  - [pylablib.core.fileio](#), 232
  - [pylablib.core.fileio.datafile](#), 202
  - [pylablib.core.fileio.dict\\_entry](#), 203
  - [pylablib.core.fileio.loadfile](#), 210
  - [pylablib.core.fileio.loadfile\\_utils](#), 216
  - [pylablib.core.fileio.location](#), 217
  - [pylablib.core.fileio.parse\\_csv](#), 222
  - [pylablib.core.fileio.savefile](#), 224
  - [pylablib.core.fileio.table\\_stream](#), 231
  - [pylablib.core.gui](#), 330
  - [pylablib.core.gui.formatter](#), 306
  - [pylablib.core.gui.limiter](#), 308



pylablib.core.gui.utils, 309  
 pylablib.core.gui.value\_handling, 311  
 pylablib.core.gui.widgets, 306  
 pylablib.core.gui.widgets.button, 232  
 pylablib.core.gui.widgets.button\_selector, 232  
 pylablib.core.gui.widgets.combo\_box, 234  
 pylablib.core.gui.widgets.container, 235  
 pylablib.core.gui.widgets.edit, 274  
 pylablib.core.gui.widgets.label, 277  
 pylablib.core.gui.widgets.layout\_manager, 279  
 pylablib.core.gui.widgets.param\_table, 284  
 pylablib.core.thread, 371  
 pylablib.core.thread.callsync, 330  
 pylablib.core.thread.controller, 341  
 pylablib.core.thread.multicast\_pool, 364  
 pylablib.core.thread.notifier, 366  
 pylablib.core.thread.profile, 366  
 pylablib.core.thread.synchronizing, 367  
 pylablib.core.thread.threadprop, 368  
 pylablib.core.thread.utils, 371  
 pylablib.core.utils, 455  
 pylablib.core.utils.array\_utils, 371  
 pylablib.core.utils.cext\_tools, 372  
 pylablib.core.utils.crc, 372  
 pylablib.core.utils.ctypes\_wrap, 372  
 pylablib.core.utils.dictionary, 376  
 pylablib.core.utils.files, 412  
 pylablib.core.utils.funcargparse, 419  
 pylablib.core.utils.functions, 420  
 pylablib.core.utils.general, 425  
 pylablib.core.utils.indexing, 433  
 pylablib.core.utils.ipc, 435  
 pylablib.core.utils.library\_parameters, 437  
 pylablib.core.utils.module, 437  
 pylablib.core.utils.nbtools, 439  
 pylablib.core.utils.net, 440  
 pylablib.core.utils.numerical, 444  
 pylablib.core.utils.observer\_pool, 445  
 pylablib.core.utils.py3, 446  
 pylablib.core.utils.rpyc\_utils, 446  
 pylablib.core.utils.strdump, 448  
 pylablib.core.utils.string, 449  
 pylablib.core.utils.strpack, 453  
 pylablib.core.utils.units, 454  
 pylablib.devices, 1034  
 pylablib.devices.Agilent, 507  
 pylablib.devices.Agilent.base, 505  
 pylablib.devices.Agilent.pressure, 505  
 pylablib.devices.AlliedVision, 522  
 pylablib.devices.AlliedVision.Bonito, 507  
 pylablib.devices.Andor, 550  
 pylablib.devices.Andor.AndorSDK2, 522  
 pylablib.devices.Andor.AndorSDK3, 534  
 pylablib.devices.Andor.atcore\_features, 549  
 pylablib.devices.Andor.base, 549  
 pylablib.devices.Andor.Shamrock, 544  
 pylablib.devices.Arcus, 563  
 pylablib.devices.Arcus.base, 550  
 pylablib.devices.Arcus.performax, 551  
 pylablib.devices.Arduino, 566  
 pylablib.devices.Arduino.base, 563  
 pylablib.devices.Attocube, 574  
 pylablib.devices.Attocube.anc300, 566  
 pylablib.devices.Attocube.anc350, 570  
 pylablib.devices.Attocube.base, 574  
 pylablib.devices.AWG, 505  
 pylablib.devices.AWG.generic, 455  
 pylablib.devices.AWG.specific, 462  
 pylablib.devices.Basler, 584  
 pylablib.devices.Basler.pylon, 574  
 pylablib.devices.BitFlow, 597  
 pylablib.devices.BitFlow.BitFlow, 584  
 pylablib.devices.Conrad, 599  
 pylablib.devices.Conrad.base, 597  
 pylablib.devices.Cryocon, 604  
 pylablib.devices.Cryocon.base, 599  
 pylablib.devices.Cryomagnetics, 613  
 pylablib.devices.Cryomagnetics.base, 604  
 pylablib.devices.DCAM, 621  
 pylablib.devices.DCAM.DCAM, 613  
 pylablib.devices.ElektroAutomatik, 625  
 pylablib.devices.ElektroAutomatik.base, 621  
 pylablib.devices.HighFinesse, 629  
 pylablib.devices.HighFinesse.wlm, 625  
 pylablib.devices.Hubner, 633  
 pylablib.devices.Hubner.base, 633  
 pylablib.devices.Hubner.Cobolt, 629  
 pylablib.devices.IMAQ, 648  
 pylablib.devices.IMAQ.IMAQ, 633  
 pylablib.devices.IMAQ.niimaq\_attrtypes, 648  
 pylablib.devices.IMAQdx, 663  
 pylablib.devices.IMAQdx.IMAQdx, 648  
 pylablib.devices.interface, 1022  
 pylablib.devices.interface.camera, 989  
 pylablib.devices.interface.stage, 1020  
 pylablib.devices.Keithley, 671  
 pylablib.devices.Keithley.base, 665  
 pylablib.devices.Keithley.multimeter, 666  
 pylablib.devices.KJL, 665  
 pylablib.devices.KJL.base, 663  
 pylablib.devices.Lakeshore, 682

`pylablib.devices.Lakeshore.base`, 671  
`pylablib.devices.LaserQuantum`, 685  
`pylablib.devices.LaserQuantum.base`, 682  
`pylablib.devices.Leybold`, 689  
`pylablib.devices.Leybold.base`, 685  
`pylablib.devices.LighthousePhotonics`, 692  
`pylablib.devices.LighthousePhotonics.base`, 689  
`pylablib.devices.Lumel`, 695  
`pylablib.devices.Lumel.base`, 692  
`pylablib.devices.M2`, 707  
`pylablib.devices.M2.base`, 695  
`pylablib.devices.M2.emm`, 697  
`pylablib.devices.M2.solstis`, 701  
`pylablib.devices.Mightex`, 714  
`pylablib.devices.Mightex.base`, 714  
`pylablib.devices.Mightex.MightexSSeries`, 707  
`pylablib.devices.Modbus`, 717  
`pylablib.devices.Modbus.modbus`, 714  
`pylablib.devices.Newport`, 739  
`pylablib.devices.Newport.base`, 735  
`pylablib.devices.Newport.picomotor`, 736  
`pylablib.devices.NI`, 725  
`pylablib.devices.NI.daq`, 717  
`pylablib.devices.NKT`, 735  
`pylablib.devices.NKT.interbus`, 725  
`pylablib.devices.Omron`, 749  
`pylablib.devices.Omron.base`, 746  
`pylablib.devices.Ophir`, 754  
`pylablib.devices.Ophir.base`, 749  
`pylablib.devices.OZOptics`, 746  
`pylablib.devices.OZOptics.base`, 739  
`pylablib.devices.PCO`, 763  
`pylablib.devices.PCO.SC2`, 754  
`pylablib.devices.Pfeiffer`, 769  
`pylablib.devices.Pfeiffer.base`, 763  
`pylablib.devices.Photometrics`, 779  
`pylablib.devices.Photometrics.pvcam`, 769  
`pylablib.devices.PhotonFocus`, 813  
`pylablib.devices.PhotonFocus.PhotonFocus`, 779  
`pylablib.devices.PhysikInstrumente`, 824  
`pylablib.devices.PhysikInstrumente.base`, 813  
`pylablib.devices.PrincetonInstruments`, 833  
`pylablib.devices.PrincetonInstruments.picamousePressEvent()`, 824  
`pylablib.devices.Rigol`, 838  
`pylablib.devices.Rigol.base`, 833  
`pylablib.devices.Rigol.power_supply`, 834  
`pylablib.devices.SiliconSoftware`, 855  
`pylablib.devices.SiliconSoftware.fgrab`, 838  
`pylablib.devices.Sirah`, 868  
`pylablib.devices.Sirah.base`, 864  
`pylablib.devices.Sirah.Matisse`, 855  
`pylablib.devices.Sirah.tuner`, 864  
`pylablib.devices.SmarAct`, 876  
`pylablib.devices.SmarAct.base`, 873  
`pylablib.devices.SmarAct.MCS2`, 868  
`pylablib.devices.SmarAct.scu3d`, 873  
`pylablib.devices.Standa`, 880  
`pylablib.devices.Standa.base`, 876  
`pylablib.devices.Tektronix`, 902  
`pylablib.devices.Tektronix.base`, 880  
`pylablib.devices.Thorlabs`, 968  
`pylablib.devices.Thorlabs.base`, 911  
`pylablib.devices.Thorlabs.elliptec`, 911  
`pylablib.devices.Thorlabs.kinesis`, 916  
`pylablib.devices.Thorlabs.misc`, 945  
`pylablib.devices.Thorlabs.serial`, 954  
`pylablib.devices.Thorlabs.TLCamera`, 902  
`pylablib.devices.Toptica`, 971  
`pylablib.devices.Toptica.base`, 968  
`pylablib.devices.Toptica.ibeam`, 968  
`pylablib.devices.Trinamic`, 980  
`pylablib.devices.Trinamic.base`, 971  
`pylablib.devices.uc480`, 1031  
`pylablib.devices.uc480.uc480`, 1022  
`pylablib.devices.utils`, 1034  
`pylablib.devices.utils.color`, 1031  
`pylablib.devices.utils.load_lib`, 1032  
`pylablib.devices.Voltcraft`, 987  
`pylablib.devices.Voltcraft.base`, 980  
`pylablib.devices.Voltcraft.multimeter`, 981  
`pylablib.devices.Windows`, 989  
`pylablib.devices.Windows.joystick`, 987  
`pylablib.widgets`, 1034  
`module (pylablib.devices.Trinamic.base.TTMCM1110ReplyData attribute)`, 972  
`month (pylablib.devices.uc480.uc480.TTimestamp attribute)`, 1024  
`motor (pylablib.devices.Thorlabs.elliptec.TMotorInfo attribute)`, 912  
`mousePressEvent()` (`pylablib.core.gui.widgets.label.EnumLabel method`), 277  
`mousePressEvent()` (`pylablib.core.gui.widgets.label.NumLabel method`), 278  
`mousePressEvent()` (`pylablib.core.gui.widgets.label.TextLabel method`), 277

`move_by()` (pylablib.devices.Arcus.performax.Performax2EXStage method), 267  
`move_by()` (pylablib.devices.Arcus.performax.Performax4EXStage method), 554  
`move_by()` (pylablib.devices.Arcus.performax.PerformaxDMXJSStage method), 561  
`move_by()` (pylablib.devices.Attocube.anc300.ANC300 method), 568  
`move_by()` (pylablib.devices.Attocube.anc350.ANC350 method), 572  
`move_by()` (pylablib.devices.Newport.picomotor.Picomotor8742 method), 737  
`move_by()` (pylablib.devices.PhysikInstrumente.base.PIE515 method), 820  
`move_by()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817  
`move_by()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`move_by()` (pylablib.devices.SmarAct.scu3d.SCU3D method), 875  
`move_by()` (pylablib.devices.Standa.base.Standa8SMC method), 879  
`move_by()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 915  
`move_by()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 929  
`move_by()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935  
`move_by()` (pylablib.devices.Trinamic.base.TMCM1110 method), 973  
`move_by()` (pylablib.devices.Trinamic.base.TMCMx110 method), 978  
`move_by_steps()` (pylablib.devices.Attocube.anc350.ANC350 method), 572  
`move_by_steps()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`move_dir()` (in module pylablib.core.utils.files), 416  
`move_file()` (in module pylablib.core.utils.files), 414  
`move_layout_element()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 244  
`move_layout_element()` (pylablib.core.gui.widgets.container.QDialogContainer method), 258  
`move_layout_element()` (pylablib.core.gui.widgets.container.QFrameContainer method), 253  
`move_layout_element()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 263  
`move_layout_element()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 267  
`move_layout_element()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 249  
`move_layout_element()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 280  
`move_layout_element()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 283  
`move_layout_element()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 294  
`move_layout_element()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 304  
`move_macrostep()` (pylablib.devices.SmarAct.scu3d.SCU3D method), 874  
`move_scan_by()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`move_scan_to()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`move_to()` (pylablib.core.utils.dictionary.DictionaryPointer method), 386  
`move_to()` (pylablib.devices.Arcus.performax.Performax2EXStage method), 559  
`move_to()` (pylablib.devices.Arcus.performax.Performax4EXStage method), 554  
`move_to()` (pylablib.devices.Arcus.performax.PerformaxDMXJSStage method), 561  
`move_to()` (pylablib.devices.Attocube.anc350.ANC350 method), 572  
`move_to()` (pylablib.devices.Newport.picomotor.Picomotor8742 method), 737  
`move_to()` (pylablib.devices.PhysikInstrumente.base.PIE515 method), 820  
`move_to()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817  
`move_to()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 871  
`move_to()` (pylablib.devices.Standa.base.Standa8SMC method), 878  
`move_to()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 914  
`move_to()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 930  
`move_to()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935  
`move_to()` (pylablib.devices.Trinamic.base.TMCM1110 method), 973  
`move_to()` (pylablib.devices.Trinamic.base.TMCMx110 method), 978  
`move_to_state()` (pylablib.core.gui.widgets.container.QWidget method), 267

`lablib.devices.Thorlabs.kinesis.MFF` method), name (pylablib.devices.Hubner.Cobolt.TDeviceInfo attribute), 924, 630  
`move_up()` (pylablib.core.utils.dictionary.DictionaryPointer method), 386, name (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649  
`multi_scale_peakdet()` (in module py- name (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 648  
`lablib.core.dataproc.feature`), 136  
`MulticastPool` (class in py- name (pylablib.devices.Lakeshore.base.TLakeshore218CurveHeader attribute), 672  
`lablib.core.thread.multicast_pool`), 364  
`MultiplexedCallable` (class in py- name (pylablib.devices.NI.daq.TDeviceInfo attribute), 718  
`lablib.core.dataproc.callable`), 130  
`MultiplexedCallable.NamesBoundCall` (class in py- name (pylablib.devices.Ophir.base.TDeviceInfo attribute), 751  
`lablib.core.dataproc.callable`), 131  
`multiplied()` (pylablib.core.dataproc.transform.Indexed2DTransform method), 162, name (pylablib.devices.Ophir.base.THeadInfo attribute), 750  
`multiplied()` (pylablib.core.dataproc.transform.LinearTransform method), 161, name (pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770  
`multiply()` (pylablib.core.dataproc.ctransform\_fallback.Chinese2DTransform method), 134, name (pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 780  
`muxaddr()` (in module py- name (pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute), 825  
`lablib.devices.Newport.picomotor`), 736  
`muxaddr()` (in module py- name (pylablib.devices.PrincetonInstruments.picam.TCameraInfo attribute), 824  
`lablib.devices.Thorlabs.elliptec`), 911  
`muxaxis()` (in module py- name (pylablib.devices.PrincetonInstruments.picam.TDeviceInfo attribute), 827  
`lablib.devices.Attocube.anc300`), 566  
`muxaxis()` (in module pylablib.devices.interface.stage), name (pylablib.devices.SiliconSoftware.fgrab.FGGrabAttribute attribute), 840  
1021  
`muxcall()` (in module pylablib.core.utils.general), 432, name (pylablib.devices.SiliconSoftware.fgrab.TAppletInfo attribute), 839  
`muxchan()` (in module pylablib.devices.Toptica.ibeam), name (pylablib.devices.SiliconSoftware.fgrab.TBoardInfo attribute), 838  
968  
`muxchannel()` (in module py- name (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute), 839  
`lablib.devices.HighFinesse.wlm`), 625  
`muxchannel()` (in module py- name (pylablib.devices.SmarAct.MCS2.TDeviceInfo attribute), 868  
`lablib.devices.Tektronix.base`), 881  
`muxchannel()` (in module py- name (pylablib.devices.Thorlabs.misc.TPMDeviceInfo attribute), 945  
`lablib.devices.Thorlabs.kinesis`), 921  
name (pylablib.devices.Thorlabs.misc.TPMSensorInfo attribute), 945  
name (pylablib.devices.Thorlabs.TLCamera.TDeviceInfo attribute), 903  
name (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987  
name (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987  
`NamedUIDGenerator` (class in py- name (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987  
`lablib.core.utils.general`), 429  
`names` (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987  
`nbuttons` (pylablib.devices.Windows.joystick.TDeviceInfo attribute), 987  
`nchannels` (pylablib.devices.Thorlabs.kinesis.TDeviceInfo attribute), 916  
`ncycles` (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920  
`ndim()` (pylablib.core.dataproc.table\_wrap.Array1DWrapper method), 154



`ndim()` (pylablib.core.dataproc.table\_wrap.Array2DWrapper attribute), 233  
`ndim()` (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper attribute), 234  
`ndim()` (pylablib.core.dataproc.table\_wrap.I1DWrapper method), 153  
`ndim()` (pylablib.core.dataproc.table\_wrap.I2DWrapper method), 156  
`ndim()` (pylablib.core.dataproc.table\_wrap.IGenWrapper method), 152  
`ndim()` (pylablib.core.dataproc.table\_wrap.Series1DWrapper method), 156  
**NetworkDeviceBackend** (class in pylablib.core.devio.comm\_backend), 181  
**new** (pylablib.devices.Windows.joystick.TJoystickEvent attribute), 987  
**new** (pylablib.devices.Windows.joystick.TJoystickEventEx attribute), 987  
**new\_backend()** (in module pylablib.core.devio.comm\_backend), 191  
**new\_frame()** (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCameraLiveBuffer attribute), 144  
**new\_messages\_number()** (pylablib.core.thread.controller.QTaskThread method), 358  
**new\_messages\_number()** (pylablib.core.thread.controller.QThreadController method), 343  
**new\_overflow()** (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.BufferManager attribute), 144  
**NewportBackendError**, 735  
**NewportError**, 735  
**next()** (pylablib.core.utils.general.AccessIterator method), 432  
**next()** (pylablib.core.utils.numerical.infinite\_list.counter method), 444  
**NIDAQ** (class in pylablib.devices.NI.daq), 718  
**NIDAQmxError**, 717  
**NIError**, 717  
**no\_stopping()** (pylablib.core.thread.controller.QTaskThread method), 358  
**no\_stopping()** (pylablib.core.thread.controller.QThreadController method), 344  
**NoControllerThreadError**, 369  
**nodes()** (pylablib.core.utils.dictionary.Dictionary method), 381  
**nodes()** (pylablib.core.utils.dictionary.DictionaryPointer method), 392  
**nodes()** (pylablib.core.utils.dictionary.FilterTree method), 409  
**nodes()** (pylablib.core.utils.dictionary.PrefixTree method), 401  
**NoMessageThreadError**, 369  
**none** (pylablib.core.gui.widgets.button\_selector.ButtonSelector attribute), 233  
**none** (pylablib.core.gui.widgets.combo\_box.ComboBox attribute), 234  
**NoParameterError**, 311  
**noreply()** (pylablib.devices.M2.base.ICEBlocDevice method), 696  
**noreply()** (pylablib.devices.M2.emm.EMM method), 700  
**noreply()** (pylablib.devices.M2.solstis.Solstis method), 706  
**normalize\_channel\_name()** (pylablib.devices.Tektronix.base.DPO2000 method), 898  
**normalize\_channel\_name()** (pylablib.devices.Tektronix.base.ITektronixScope method), 881  
**normalize\_channel\_name()** (pylablib.devices.Tektronix.base.TDS2000 method), 891  
**normalize\_fourier\_transform()** (in module pylablib.core.dataproc.fourier), 144  
**normalize\_path()** (in module pylablib.core.utils.dictionary), 376  
**normalize\_path()** (in module pylablib.core.utils.files), 413  
**normalize\_path\_entry()** (in module pylablib.core.utils.dictionary), 376  
**notes** (pylablib.devices.Thorlabs.kinesis.TDeviceInfo attribute), 144  
**notify()** (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330  
**notify()** (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331  
**notify()** (pylablib.core.thread.callsync.QDummyResultSynchronizer method), 331  
**notify()** (pylablib.core.thread.notifier.ISkippableNotifier method), 366  
**notify()** (pylablib.core.thread.synchronizing.QMultiThreadNotifier method), 368  
**notify()** (pylablib.core.thread.synchronizing.QThreadNotifier method), 367  
**notify()** (pylablib.core.utils.observer\_pool.ObserverPool method), 446  
**notify()** (pylablib.devices.PCO.SC2.PCOS2Camera.ScheduleLooper method), 756  
**notify\_exec\_point()** (pylablib.core.thread.controller.QTaskThread method), 358  
**notify\_exec\_point()** (pylablib.core.thread.controller.QThreadController method), 348  
**notifying\_state()** (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330

notifying\_state() (pylablib.core.thread.callsync.QDirectResultSynchronizer attribute), 332  
 notifying\_state() (pylablib.core.thread.notifier.ISkippableNotifier method), 366  
 notifying\_state() (pylablib.core.thread.synchronizing.QThreadNotifier method), 367  
 nrois (pylablib.devices.PrincetonInstruments.picam.TROIConstraints attribute), 825  
 num\_bk (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920  
 num\_fw (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920  
 NumberLimit (class in pylablib.core.gui.limiter), 308  
 NumEdit (class in pylablib.core.gui.widgets.edit), 275  
 NumLabel (class in pylablib.core.gui.widgets.label), 278  
 NumpyIndex (class in pylablib.core.utils.indexing), 433  
**O**  
 obj (pylablib.devices.ElektroAutomatik.base.PS2000B.TTelegram attribute), 623  
 obj\_prop() (in module pylablib.core.utils.functions), 424  
 ObserverPool (class in pylablib.core.utils.observer\_pool), 445  
 ObserverPool.Observer (class in pylablib.core.utils.observer\_pool), 445  
 obtain() (in module pylablib.core.utils.rpyc\_utils), 446  
 obtain() (pylablib.core.utils.rpyc\_utils.DeviceService method), 447  
 obtain() (pylablib.core.utils.rpyc\_utils.SocketTunnelService method), 447  
 ocp (pylablib.devices.ElektroAutomatik.base.TStatus attribute), 622  
 off\_delay (pylablib.devices.Standa.base.TPowerParams attribute), 877  
 off\_enabled (pylablib.devices.Standa.base.TPowerParams attribute), 877  
 off\_thresh (pylablib.devices.Pfeiffer.base.TTPG260GaugeControlSettings attribute), 764  
 offset (pylablib.core.utils.ipc.TShmemVarDesc attribute), 436  
 offset (pylablib.devices.Andor.Shamrock.TGratingInfo attribute), 545  
 offset (pylablib.devices.Thorlabs.TLCamera.TFrameInfo attribute), 903  
 offset\_distance (pylablib.devices.Thorlabs.kinesis.THomeParams attribute), 919  
 old (pylablib.devices.Windows.joystick.TJoystickEvent attribute), 987  
 old (pylablib.devices.Windows.joystick.TJoystickEventEx attribute), 987  
 OmronE5xCController (class in pylablib.devices.Omron.base), 746  
 on\_connect() (pylablib.core.utils.rpyc\_utils.DeviceService method), 447  
 on\_connect() (pylablib.core.utils.rpyc\_utils.SocketTunnelService method), 447  
 on\_disconnect() (pylablib.core.utils.rpyc\_utils.DeviceService method), 447  
 on\_disconnect() (pylablib.core.utils.rpyc\_utils.SocketTunnelService method), 447  
 on\_finish() (pylablib.core.thread.controller.QTaskThread method), 353  
 on\_finish() (pylablib.core.thread.controller.QThreadController method), 344  
 on\_overflow() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 539  
 on\_start() (pylablib.core.thread.controller.QTaskThread method), 353  
 on\_start() (pylablib.core.thread.controller.QThreadController method), 344  
 on\_thresh (pylablib.devices.Pfeiffer.base.TTPG260GaugeControlSettings attribute), 764  
 opcode (pylablib.devices.Attocube.anc350.ANC350.Telegram attribute), 570  
 open() (pylablib.core.devio.comm\_backend.FT232DeviceBackend method), 179  
 open() (pylablib.core.devio.comm\_backend.HIDDeviceBackend method), 187  
 open() (pylablib.core.devio.comm\_backend.ICommBackendWrapper method), 192  
 open() (pylablib.core.devio.comm\_backend.IDeviceCommBackend method), 171  
 open() (pylablib.core.devio.comm\_backend.NetworkDeviceBackend method), 181  
 open() (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 184  
 open() (pylablib.core.devio.comm\_backend.RecordedDeviceBackend method), 189  
 open() (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 176  
 open() (pylablib.core.devio.comm\_backend.VisaDeviceBackend method), 173  
 open() (pylablib.core.devio.hid.HIDDevice method), 194  
 open() (pylablib.core.devio.interface.IDevice method), 196  
 open() (pylablib.core.devio.SCPI.SCPIDevice method), 168  
 open() (pylablib.core.fileio.location.FolderFileSystemDataLocation method), 222  
 open() (pylablib.core.fileio.location.IDataLocation method), 222

- method), 218
- `open()` (`pylablib.core.fileio.location.IFileSystemDataLocation` method), 219
- `open()` (`pylablib.core.fileio.location.LocationFile` method), 218
- `open()` (`pylablib.core.fileio.location.OpenedFileLocation` method), 219
- `open()` (`pylablib.core.fileio.location.PrefixedFileSystemDataLocation` method), 221
- `open()` (`pylablib.core.fileio.location.SingleFileSystemDataLocation` method), 220
- `open()` (`pylablib.devices.Agilent.pressure.XGS600` method), 507
- `open()` (`pylablib.devices.AlliedVision.Bonito.BonitoIMACamera` method), 518
- `open()` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` method), 508
- `open()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 524
- `open()` (`pylablib.devices.Andor.AndorSDK2.LibraryController` method), 522
- `open()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera` method), 537
- `open()` (`pylablib.devices.Andor.AndorSDK3.LibraryController` method), 534
- `open()` (`pylablib.devices.Andor.Shamrock.LibraryController` method), 544
- `open()` (`pylablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 545
- `open()` (`pylablib.devices.Arcus.performax.GenericPerformaxCamera` method), 551
- `open()` (`pylablib.devices.Arcus.performax.Performax2EXStage` method), 559
- `open()` (`pylablib.devices.Arcus.performax.Performax4EXStage` method), 556
- `open()` (`pylablib.devices.Arcus.performax.PerformaxDMX.ISpectrograph` method), 563
- `open()` (`pylablib.devices.Arduino.base.IArduinoDevice` method), 565
- `open()` (`pylablib.devices.Attocube.anc300.ANC300` method), 566
- `open()` (`pylablib.devices.Attocube.anc350.ANC350` method), 573
- `open()` (`pylablib.devices.AWG.generic.GenericAWG` method), 460
- `open()` (`pylablib.devices.AWG.specific.Agilent33220A` method), 471
- `open()` (`pylablib.devices.AWG.specific.Agilent33500` method), 465
- `open()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 483
- `open()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 477
- `open()` (`pylablib.devices.AWG.specific.RigolDG1000` method), 501
- `open()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 489
- `open()` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 495
- `open()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera` method), 578
- `open()` (`pylablib.devices.Basler.pylon.LibraryController` method), 574
- `open()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera` method), 594
- `open()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber` method), 585
- `open()` (`pylablib.devices.Conrad.base.RelayBoard` method), 597
- `open()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 602
- `open()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 606
- `open()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 610
- `open()` (`pylablib.devices.DCAM.DCAM.DCAMCamera` method), 615
- `open()` (`pylablib.devices.DCAM.DCAM.LibraryController` method), 613
- `open()` (`pylablib.devices.ElektroAutomatik.base.PS2000B` method), 623
- `open()` (`pylablib.devices.HighFinesse.wlm.WLM` method), 626
- `open()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 632
- `open()` (`pylablib.devices.IMAQ.IMAQ.IMAQCamera` method), 645
- `open()` (`pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` method), 634
- `open()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera` method), 660
- `open()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera` method), 651
- `open()` (`pylablib.devices.interface.camera.IAttributeCamera` method), 998
- `open()` (`pylablib.devices.interface.camera.IBinROICamera` method), 1017
- `open()` (`pylablib.devices.interface.camera.ICamera` method), 994
- `open()` (`pylablib.devices.interface.camera.IExposureCamera` method), 1008
- `open()` (`pylablib.devices.interface.camera.IGrabberAttributeCamera` method), 1003
- `open()` (`pylablib.devices.interface.camera.IROICamera` method), 1013
- `open()` (`pylablib.devices.interface.stage.IMultiaxisStage` method), 1022
- `open()` (`pylablib.devices.interface.stage.IStage` method),

- 1021
- `open()` (`pylablib.devices.Keithley.multimeter.Keithley2110` method), 669
- `open()` (`pylablib.devices.KJL.base.KJL300` method), 665
- `open()` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 675
- `open()` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 680
- `open()` (`pylablib.devices.LaserQuantum.base.Finesse` method), 684
- `open()` (`pylablib.devices.Leybold.base.GenericITR` method), 687
- `open()` (`pylablib.devices.Leybold.base.ITR90` method), 689
- `open()` (`pylablib.devices.LighthousePhotonics.base.SproutG` method), 691
- `open()` (`pylablib.devices.Lumel.base.LumelRE72Controller` method), 694
- `open()` (`pylablib.devices.M2.base.ICEBlocDevice` method), 696
- `open()` (`pylablib.devices.M2.emm.EMM` method), 700
- `open()` (`pylablib.devices.M2.solstis.Solstis` method), 706
- `open()` (`pylablib.devices.Mightex.MightexSSeries.LibraryController` method), 708
- `open()` (`pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera` method), 708
- `open()` (`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` method), 717
- `open()` (`pylablib.devices.Newport.picomotor.Picomotor8742` method), 739
- `open()` (`pylablib.devices.NI.daq.NIDAQ` method), 718
- `open()` (`pylablib.devices.NKT.interbus.GenericInterbusDevice` method), 727
- `open()` (`pylablib.devices.NKT.interbus.GenericInterbusModule` method), 729
- `open()` (`pylablib.devices.NKT.interbus.IInterbusModule` method), 728
- `open()` (`pylablib.devices.NKT.interbus.InterbusSystem` method), 735
- `open()` (`pylablib.devices.NKT.interbus.SuperKExtremeInterbusModule` method), 730
- `open()` (`pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule` method), 731
- `open()` (`pylablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule` method), 732
- `open()` (`pylablib.devices.NKT.interbus.SuperKSelectInterbusModule` method), 733
- `open()` (`pylablib.devices.Omron.base.OmronE5xCCController` method), 748
- `open()` (`pylablib.devices.Ophir.base.OphirDevice` method), 750
- `open()` (`pylablib.devices.Ophir.base.VegaPowerMeter` method), 754
- `open()` (`pylablib.devices.OZOptics.base.DD100` method), 744
- `open()` (`pylablib.devices.OZOptics.base.EPC04` method), 746
- `open()` (`pylablib.devices.OZOptics.base.OZOpticsDevice` method), 741
- `open()` (`pylablib.devices.OZOptics.base.TF100` method), 742
- `open()` (`pylablib.devices.PCO.SC2.PCOSC2Camera` method), 755
- `open()` (`pylablib.devices.Pfeiffer.base.DPG202` method), 768
- `open()` (`pylablib.devices.Pfeiffer.base.TPG260` method), 767
- `open()` (`pylablib.devices.Photometrics.pvcam.LibraryController` method), 769
- `open()` (`pylablib.devices.Photometrics.pvcam.PvcamCamera` method), 772
- `open()` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` method), 782
- `open()` (`pylablib.devices.PhotonFocus.PhotonFocus.LibraryController` method), 779
- `open()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera` method), 805
- `open()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera` method), 788
- `open()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera` method), 797
- `open()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` method), 814
- `open()` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 819
- `open()` (`pylablib.devices.PhysikInstrumente.base.PIE516` method), 818
- `open()` (`pylablib.devices.PrincetonInstruments.picam.LibraryController` method), 824
- `open()` (`pylablib.devices.PrincetonInstruments.picam.PicamCamera` method), 828
- `open()` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 836
- `open()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera` method), 852
- `open()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` method), 841
- `open()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 862
- `open()` (`pylablib.devices.SmarAct.MCS2.LibraryController` method), 868
- `open()` (`pylablib.devices.SmarAct.MCS2.MCS2` method), 869
- `open()` (`pylablib.devices.SmarAct.scu3d.LibraryController` method), 873
- `open()` (`pylablib.devices.SmarAct.scu3d.SCU3D` method), 874
- `open()` (`pylablib.devices.Standa.base.Standa8SMC` method), 874



- method), 880
- `open()` (pylablib.devices.Tektronix.base.DPO2000 method), 898
- `open()` (pylablib.devices.Tektronix.base.ITektronixScope method), 886
- `open()` (pylablib.devices.Tektronix.base.TDS2000 method), 891
- `open()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 915
- `open()` (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 918
- `open()` (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 923
- `open()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 933
- `open()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 940
- `open()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 937
- `open()` (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 944
- `open()` (pylablib.devices.Thorlabs.kinesis.MFF method), 926
- `open()` (pylablib.devices.Thorlabs.misc.GenericPM method), 946
- `open()` (pylablib.devices.Thorlabs.misc.PM160 method), 952
- `open()` (pylablib.devices.Thorlabs.serial.FW method), 959
- `open()` (pylablib.devices.Thorlabs.serial.FWv1 method), 962
- `open()` (pylablib.devices.Thorlabs.serial.MDT69xA method), 966
- `open()` (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 954
- `open()` (pylablib.devices.Thorlabs.TLCamera.LibraryController method), 902
- `open()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 903
- `open()` (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 969
- `open()` (pylablib.devices.Trinamic.base.TMCM1110 method), 972
- `open()` (pylablib.devices.Trinamic.base.TMCMx110 method), 978
- `open()` (pylablib.devices.uc480.uc480.UC480Camera method), 1025
- `open()` (pylablib.devices.utils.load\_lib.LibraryController method), 1033
- `open()` (pylablib.devices.Voltcraft.multimeter.VC7055 method), 982
- `open()` (pylablib.devices.Voltcraft.multimeter.VC880 method), 986
- `open()` (pylablib.devices.Windows.joystick.Joystick method), 988
- `open_loop_out` (pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutput attribute), 942
- `open_result` (pylablib.devices.utils.load\_lib.TLibraryOpenResult attribute), 1033
- `opened` (pylablib.core.fileio.location.LocationFile attribute), 218
- `OpenedFileLocation` (class in pylablib.core.fileio.location), 219
- `OphirBackendError`, 749
- `OphirDevice` (class in pylablib.devices.Ophir.base), 749
- `OphirError`, 749
- `opid` (pylablib.devices.utils.load\_lib.TLibraryOpenResult attribute), 1033
- `opp` (pylablib.devices.ElektroAutomatik.base.TStatus attribute), 622
- `order_to_pos()` (in module pylablib.core.gui.formatter), 306
- `otp` (pylablib.devices.ElektroAutomatik.base.TStatus attribute), 622
- `overflows` (pylablib.devices.Andor.AndorSDK3.TMissedFramesStatus attribute), 536
- `overruns` (pylablib.devices.PCO.SC2.TInternalBufferStatus attribute), 755
- `oversamp` (pylablib.devices.Sirah.Matisse.TPiezoetDriveParameters attribute), 855
- `oversamp` (pylablib.devices.Sirah.Matisse.TRefcellWaveformParameters attribute), 856
- `ovp` (pylablib.devices.ElektroAutomatik.base.TStatus attribute), 623
- `OZOpticsBackendError`, 740
- `OZOpticsDevice` (class in pylablib.devices.OZOptics.base), 740
- `OZOpticsError`, 739
- P**
- `P` (pylablib.devices.Sirah.Matisse.TPiezoetFeedbackParameters attribute), 855
- `P` (pylablib.devices.Sirah.Matisse.TSlowpiezoCtlParameters attribute), 855
- `P` (pylablib.devices.Sirah.Matisse.TThinectlParameters attribute), 855
- `p` (pylablib.devices.Thorlabs.kinesis.TQuadDetectorPIDParams attribute), 942
- `pack_int()` (in module pylablib.core.utils.strpack), 453
- `pack_uint()` (in module pylablib.core.utils.strpack), 453
- `pad_borders()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 285
- `pad_borders()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 305
- `pad_trace()` (in module pylablib.core.dataproc.utils), 165

page	(pylablib.devices.Leybold.base.TDeviceInfo attribute), 685	lablib.devices.Lakeshore.base.Lakeshore218 static method), 675
param1	(pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice attribute), 917	param1 (pylablib.devices.Lakeshore.base.Lakeshore370 static method), 680
param2	(pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice attribute), 917	param2 (pylablib.devices.Lakeshore.base.Lakeshore370 static method), 680
parameter_range_error()	(in module py-lablib.core.utils.funcargparse), 419	parse_array_data() (py-lablib.devices.PhysikInstrumente.base.PIE515 static method), 822
parameter_value_error()	(in module py-lablib.core.utils.funcargparse), 419	parse_array_data() (py-lablib.devices.Rigol.power_supply.DP1116A static method), 836
ParamTable	(class in py-lablib.core.gui.widgets.param_table), 284	parse_array_data() (py-lablib.devices.Sirah.Matisse.SirahMatisse static method), 862
ParamTable.ParamRow	(class in py-lablib.core.gui.widgets.param_table), 285	parse_array_data() (py-lablib.devices.Tektronix.base.DPO2000 static method), 898
parse_array_data()	(py-lablib.core.devio.SCPI.SCPIDevice static method), 169	parse_array_data() (py-lablib.devices.Tektronix.base.ITektronixScope static method), 886
parse_array_data()	(py-lablib.devices.AWG.generic.GenericAWG static method), 460	parse_array_data() (py-lablib.devices.Tektronix.base.TDS2000 static method), 891
parse_array_data()	(py-lablib.devices.AWG.specific.Agilent33220A static method), 471	parse_array_data() (py-lablib.devices.Thorlabs.misc.GenericPM static method), 948
parse_array_data()	(py-lablib.devices.AWG.specific.Agilent33500 static method), 465	parse_array_data() (py-lablib.devices.Thorlabs.misc.PM160 static method), 952
parse_array_data()	(py-lablib.devices.AWG.specific.InstekAFG2000 static method), 483	parse_array_data() (py-lablib.devices.Thorlabs.serial.FW static method), 959
parse_array_data()	(py-lablib.devices.AWG.specific.InstekAFG2225 static method), 477	parse_array_data() (py-lablib.devices.Thorlabs.serial.FWv1 static method), 963
parse_array_data()	(py-lablib.devices.AWG.specific.RigolDG1000 static method), 502	parse_array_data() (py-lablib.devices.Thorlabs.serial.MDT69xA static method), 966
parse_array_data()	(py-lablib.devices.AWG.specific.RSInstekAFG21000 static method), 489	parse_array_data() (py-lablib.devices.Thorlabs.serial.ThorlabsSerialInterface static method), 955
parse_array_data()	(py-lablib.devices.AWG.specific.TektronixAFG1000 static method), 495	parse_array_data() (py-lablib.devices.Voltcraft.multimeter.VC7055 static method), 982
parse_array_data()	(py-lablib.devices.Cryocon.base.Cryocon1x static method), 602	parse_dict_line() (in module py-lablib.core.fileio.loadfile_utils), 216
parse_array_data()	(py-lablib.devices.Cryomagnetics.base.LM500 static method), 606	parse_float() (in module pylablib.core.gui.formatter), 306
parse_array_data()	(py-lablib.devices.Cryomagnetics.base.LM510 static method), 610	parse_metainfo_v1() (in module py-lablib.devices.Photometrics.pvcam), 779
parse_array_data()	(py-lablib.devices.Keithley.multimeter.Keithley2110 static method), 669	parse_metainfo_v3() (in module py-lablib.devices.Photometrics.pvcam), 779
parse_array_data()	(py-lablib.devices.Lakeshore.base.Lakeshore218 static method), 675	parse_stored_table_data() (in module py-lablib.core.fileio.dict_entry), 204

part (pylablib.devices.Photometrics.pvcam.TDeviceInfo attribute), 771  
 partition\_list() (in module pylablib.core.utils.general), 426  
 pass\_result (pylablib.core.thread.callsync.QScheduledCall.Callback attribute), 332  
 passed() (pylablib.core.utils.general.Countdown method), 430  
 passed() (pylablib.core.utils.general.Timer method), 430  
 path (pylablib.core.devio.hid.TDeviceInfoDescription attribute), 194  
 path (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute), 839  
 paths() (pylablib.core.utils.dictionary.Dictionary method), 381  
 paths() (pylablib.core.utils.dictionary.DictionaryPointer method), 392  
 paths() (pylablib.core.utils.dictionary.FilterTree method), 409  
 paths() (pylablib.core.utils.dictionary.PrefixTree method), 401  
 paths\_equal() (in module pylablib.core.utils.files), 413  
 pause() (pylablib.core.thread.controller.QTaskThread.Job method), 352  
 pausing() (pylablib.core.devio.hid.HIDevice.Reader method), 195  
 pausing\_acquisition() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 518  
 pausing\_acquisition() (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 511  
 pausing\_acquisition() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 532  
 pausing\_acquisition() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 542  
 pausing\_acquisition() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 582  
 pausing\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 594  
 pausing\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 589  
 pausing\_acquisition() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 620  
 pausing\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 645  
 pausing\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 639  
 pausing\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 660  
 pausing\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 655  
 pausing\_acquisition() (pylablib.devices.interface.camera.IAttributeCamera method), 998  
 pausing\_acquisition() (pylablib.devices.interface.camera.IBinROICamera method), 1017  
 pausing\_acquisition() (pylablib.devices.interface.camera.ICamera method), 990  
 pausing\_acquisition() (pylablib.devices.interface.camera.IExposureCamera method), 1008  
 pausing\_acquisition() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1003  
 pausing\_acquisition() (pylablib.devices.interface.camera.IROICamera method), 1013  
 pausing\_acquisition() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 712  
 pausing\_acquisition() (pylablib.devices.PCO.SC2.PCOSC2Camera method), 761  
 pausing\_acquisition() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 777  
 pausing\_acquisition() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 786  
 pausing\_acquisition() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 810  
 pausing\_acquisition() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 793  
 pausing\_acquisition() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 802  
 pausing\_acquisition() (pylablib.devices.PrincetonInstruments.picam.PicamCamera method), 832  
 pausing\_acquisition() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera method), 852

pausing\_acquisition() (py- PhysikInstrumenteError, 813  
 lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareGrabber (class in py-  
 method), 846 lablib.devices.PrincetonInstruments.picam),  
 pausing\_acquisition() (py- 825  
 lablib.devices.Thorlabs.TLCamera.ThorlabsTLCameraPicamCamera (class in py-  
 method), 909 lablib.devices.PrincetonInstruments.picam),  
 pausing\_acquisition() (py- 827  
 lablib.devices.uc480.uc480.UC480Camera Picomotor8742 (class in py-  
 method), 1029 lablib.devices.Newport.picomotor), 736  
 payload (pylablib.devices.NKT.interbus.TInterbusTelegramPIE515 (class in pylablib.devices.PhysikInstrumente.base),  
 attribute), 725 819  
 payload (pylablib.devices.Voltcraft.multimeter.VC880.TMProbePIE516 (class in pylablib.devices.PhysikInstrumente.base),  
 attribute), 985 816  
 PCOSC2Camera (class in pylablib.devices.PCO.SC2), 755  
 PCOSC2Camera.BufferManager (class in py-  
 lablib.devices.PCO.SC2), 756  
 PCOSC2Camera.ScheduleLooper (class in py-  
 lablib.devices.PCO.SC2), 756  
 Peak (class in pylablib.core.dataproc.feature), 135  
 peaks\_sum\_func() (in module py-  
 lablib.core.dataproc.feature), 135  
 Performax2EXStage (class in py-  
 lablib.devices.Arcus.performax), 556  
 Performax4EXStage (class in py-  
 lablib.devices.Arcus.performax), 552  
 PerformaxDMXJSASStage (class in py-  
 lablib.devices.Arcus.performax), 560  
 period (pylablib.core.gui.widgets.container.TTimer at-  
 tribute), 235  
 PFCamAttribute (class in py-  
 lablib.devices.PhotonFocus.PhotonFocus),  
 780  
 PfeifferBackendError, 763  
 PfeifferError, 763  
 phase (pylablib.devices.Sirah.Matisse.TPiezoetFeedbackParameters method), 348  
 attribute), 855  
 phase (pylablib.devices.Sirah.Matisse.TPiezoetFeedforwardParameters method), 348  
 attribute), 855  
 PhotonFocusBitFlowCamera (class in py-  
 lablib.devices.PhotonFocus.PhotonFocus),  
 805  
 PhotonFocusBitFlowCamera.BufferManager (class  
 in pylablib.devices.PhotonFocus.PhotonFocus),  
 806  
 PhotonFocusIMAQCamera (class in py-  
 lablib.devices.PhotonFocus.PhotonFocus),  
 788  
 PhotonFocusSiSoCamera (class in py-  
 lablib.devices.PhotonFocus.PhotonFocus),  
 797  
 PhotonFocusSiSoCamera.BufferManager (class in  
 pylablib.devices.PhotonFocus.PhotonFocus),  
 797  
 PhysikInstrumenteBackendError, 814  
 pip\_install() (in module pylablib.core.utils.module),  
 438  
 PipeIPCChannel (class in pylablib.core.utils.ipc), 435  
 pixelclock (pylablib.devices.Thorlabs.TLCamera.TFrameInfo  
 attribute), 903  
 pixeltype (pylablib.devices.Andor.AndorSDK3.TFrameInfo  
 attribute), 536  
 pixeltype (pylablib.devices.DCAM.DCAM.TFrameInfo  
 attribute), 615  
 pixeltype (pylablib.devices.Thorlabs.TLCamera.TFrameInfo  
 attribute), 903  
 place\_widget\_at\_location() (in module py-  
 lablib.core.gui.utils), 309  
 platform (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo  
 attribute), 839  
 PM160 (class in pylablib.devices.Thorlabs.misc), 950  
 points (pylablib.devices.Lakeshore.base.TLakeshore218FilterSettings  
 attribute), 672  
 poke() (pylablib.core.thread.controller.QTaskThread  
 method), 358  
 poke() (pylablib.core.thread.controller.QThreadController  
 method), 358  
 polynomial() (in module py-  
 lablib.core.utils.numerical), 445  
 pop() (pylablib.core.utils.dictionary.Dictionary  
 method), 378  
 pop() (pylablib.core.utils.dictionary.DictionaryPointer  
 method), 392  
 pop() (pylablib.core.utils.dictionary.FilterTree method),  
 409  
 pop() (pylablib.core.utils.dictionary.PrefixTree method),  
 401  
 pop\_call() (pylablib.core.thread.callsync.QQueueLengthLimitScheduler  
 method), 337  
 pop\_call() (pylablib.core.thread.callsync.QQueueScheduler  
 method), 335  
 pop\_call() (pylablib.core.thread.callsync.QQueueSizeLimitScheduler  
 method), 338  
 pop\_message() (pylablib.core.thread.controller.QTaskThread  
 method), 359  
 pop\_message() (pylablib.core.thread.controller.QThreadController  
 method), 359



method), 343

port (pylablib.devices.PhotonFocus.PhotonFocus.TCameraInfo attribute), 780

port\_idx (pylablib.devices.Photometrics.pvcam.TReadoutInfo attribute), 772

port\_name (pylablib.devices.Photometrics.pvcam.TReadoutInfo attribute), 772

pos\_to\_order() (in module pylablib.core.gui.formatter), 306

position (pylablib.core.dataproc.feature.Baseline attribute), 135

position (pylablib.core.dataproc.feature.Peak attribute), 135

position (pylablib.core.gui.utils.TWidgetLocation attribute), 309

position (pylablib.devices.DCAM.DCAM.TFrameInfo attribute), 615

position (pylablib.devices.Standa.base.TFullState attribute), 877

post\_open() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 578

post\_open() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 657

post\_open() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 651

power (pylablib.devices.ElektroAutomatik.base.TOutputLimit attribute), 622

power\_off() (pylablib.devices.Standa.base.Standa8SMC method), 879

power\_spectral\_density() (in module pylablib.core.dataproc.fourier), 146

power\_up (pylablib.devices.Toptica.ibeam.TWorkHours attribute), 968

pquery() (pylablib.devices.Standa.base.Standa8SMC method), 878

precede() (pylablib.core.dataproc.ctransform\_fallback.CLImage2D method), 134

preceded() (pylablib.core.dataproc.transform.Indexed2DTransform method), 162

preceded() (pylablib.core.dataproc.transform.LinearTransform method), 161

PrefixedFileSystemDataLocation (class in pylablib.core.fileio.location), 220

PrefixShortcutTree (class in pylablib.core.utils.dictionary), 411

PrefixTree (class in pylablib.core.utils.dictionary), 394

preinit() (pylablib.devices.Andor.AndorSDK2.LibraryController method), 522

preinit() (pylablib.devices.Andor.AndorSDK3.LibraryController method), 534

preinit() (pylablib.devices.Andor.Shamrock.LibraryController method), 544

preinit() (pylablib.devices.Basler.pylon.LibraryController method), 574

preinit() (pylablib.devices.DCAM.DCAM.LibraryController method), 613

preinit() (pylablib.devices.Mightex.MightexSSeries.LibraryController method), 708

preinit() (pylablib.devices.Photometrics.pvcam.LibraryController method), 769

preinit() (pylablib.devices.PhotonFocus.PhotonFocus.LibraryController method), 779

preinit() (pylablib.devices.PrincetonInstruments.picam.LibraryController method), 824

preinit() (pylablib.devices.SmarAct.MCS2.LibraryController method), 868

preinit() (pylablib.devices.SmarAct.scu3d.LibraryController method), 873

preinit() (pylablib.devices.Thorlabs.TLCamera.LibraryController method), 902

preinit() (pylablib.devices.utils.load\_lib.LibraryController method), 1033

prep() (pylablib.core.utils.ctypes\_wrap.CStructWrapper method), 375

prep\_struct() (pylablib.core.utils.ctypes\_wrap.CStructWrapper method), 375

prep\_struct\_args() (pylablib.core.utils.ctypes\_wrap.CStructWrapper class method), 375

presets (pylablib.devices.Ophir.base.TWavelengthInfo attribute), 751

print\_stats() (in module pylablib.core.thread.profile), 367

priority (pylablib.core.thread.controller.QTaskThread.TBatchJob attribute), 351

priority (pylablib.core.thread.controller.QTaskThread.TCommand attribute), 351

priority (pylablib.core.utils.observer\_pool.ObserverPool.Observer attribute), 445

process\_interrupt() (pylablib.core.thread.controller.QTaskThread method), 359

process\_interrupt() (pylablib.core.thread.controller.QThreadController method), 344

process\_message() (pylablib.core.thread.controller.QTaskThread method), 359

process\_message() (pylablib.core.thread.controller.QThreadController method), 344

product (pylablib.core.devio.hid.TDeviceDescription attribute), 194

product (pylablib.devices.LighthousePhotonics.base.TDeviceInfo attribute), 690

product (pylablib.devices.Photometrics.pvcam.TDeviceInfo attribute), 771

product\_id (pylablib.core.devio.hid.TDeviceDescription

attribute), 194

ProgressBarValueHandler (class in pylablib.core.gui.value\_handling), 324

PropertyValueHandler (class in pylablib.core.gui.value\_handling), 313

props (pylablib.devices.Basler.pylon.TCameraInfo attribute), 575

props (pylablib.devices.Basler.pylon.TDeviceInfo attribute), 577

PS2000B (class in pylablib.devices.ElektroAutomatik.base), 623

PS2000B.TTelegram (class in pylablib.devices.ElektroAutomatik.base), 623

pstep (pylablib.devices.interface.camera.TAxisROILimit attribute), 1010

psu (pylablib.devices.LaserQuantum.base.TTemperatures attribute), 683

psu (pylablib.devices.LaserQuantum.base.TWorkHours attribute), 682

pulse (pylablib.devices.Thorlabs.elliptec.TDeviceInfo attribute), 911

pulse\_divisor (pylablib.devices.Trinamic.base.TVelocityParam attribute), 972

PushButtonValueHandler (class in pylablib.core.gui.value\_handling), 321

pval() (in module pylablib.core.devio.interface), 202

PvcamAttribute (class in pylablib.devices.Photometrics.pvcam), 769

PvcamCamera (class in pylablib.devices.Photometrics.pvcam), 772

pylablib  
module, 1034

pylablib.core  
module, 455

pylablib.core.dataproc  
module, 165

pylablib.core.dataproc.callable  
module, 129

pylablib.core.dataproc.ctransform\_fallback  
module, 134

pylablib.core.dataproc.feature  
module, 135

pylablib.core.dataproc.filters  
module, 137

pylablib.core.dataproc.fitting  
module, 141

pylablib.core.dataproc.fourier  
module, 144

pylablib.core.dataproc.iir\_transform  
module, 147

pylablib.core.dataproc.image  
module, 147

pylablib.core.dataproc.interpolate  
module, 148

pylablib.core.dataproc.specfunc  
module, 151

pylablib.core.dataproc.table\_wrap  
module, 152

pylablib.core.dataproc.transform  
module, 161

pylablib.core.dataproc.utils  
module, 162

pylablib.core.devio  
module, 202

pylablib.core.devio.backend\_logger  
module, 169

pylablib.core.devio.base  
module, 170

pylablib.core.devio.comm\_backend  
module, 170

pylablib.core.devio.data\_format  
module, 193

pylablib.core.devio.hid  
module, 194

pylablib.core.devio.hid\_base  
module, 196

pylablib.core.devio.interface  
module, 196

pylablib.core.devio.SCPi  
module, 165

pylablib.core.fileio  
module, 232

pylablib.core.fileio.datafile  
module, 202

pylablib.core.fileio.dict\_entry  
module, 203

pylablib.core.fileio.loadfile  
module, 210

pylablib.core.fileio.loadfile\_utils  
module, 216

pylablib.core.fileio.location  
module, 217

pylablib.core.fileio.parse\_csv  
module, 222

pylablib.core.fileio.savefile  
module, 224

pylablib.core.fileio.table\_stream  
module, 231

pylablib.core.gui  
module, 330

pylablib.core.gui.formatter  
module, 306

pylablib.core.gui.limiter  
module, 308

pylablib.core.gui.utils  
module, 309

pylablib.core.gui.value\_handling  
module, 311

pylablib.core.gui.widgets  
module, 306

pylablib.core.gui.widgets.button  
module, 232

pylablib.core.gui.widgets.button\_selector  
module, 232

pylablib.core.gui.widgets.combo\_box  
module, 234

pylablib.core.gui.widgets.container  
module, 235

pylablib.core.gui.widgets.edit  
module, 274

pylablib.core.gui.widgets.label  
module, 277

pylablib.core.gui.widgets.layout\_manager  
module, 279

pylablib.core.gui.widgets.param\_table  
module, 284

pylablib.core.thread  
module, 371

pylablib.core.thread.callsync  
module, 330

pylablib.core.thread.controller  
module, 341

pylablib.core.thread.multicast\_pool  
module, 364

pylablib.core.thread.notifier  
module, 366

pylablib.core.thread.profile  
module, 366

pylablib.core.thread.synchronizing  
module, 367

pylablib.core.thread.threadprop  
module, 368

pylablib.core.thread.utils  
module, 371

pylablib.core.utils  
module, 455

pylablib.core.utils.array\_utils  
module, 371

pylablib.core.utils.cext\_tools  
module, 372

pylablib.core.utils.crc  
module, 372

pylablib.core.utils.ctypes\_wrap  
module, 372

pylablib.core.utils.dictionary  
module, 376

pylablib.core.utils.files  
module, 412

pylablib.core.utils.funcargparse  
module, 419

pylablib.core.utils.functions  
module, 420

pylablib.core.utils.general  
module, 425

pylablib.core.utils.indexing  
module, 433

pylablib.core.utils.ipc  
module, 435

pylablib.core.utils.library\_parameters  
module, 437

pylablib.core.utils.module  
module, 437

pylablib.core.utils.nbtools  
module, 439

pylablib.core.utils.net  
module, 440

pylablib.core.utils.numerical  
module, 444

pylablib.core.utils.observer\_pool  
module, 445

pylablib.core.utils.py3  
module, 446

pylablib.core.utils.rpyc\_utils  
module, 446

pylablib.core.utils.strdump  
module, 448

pylablib.core.utils.string  
module, 449

pylablib.core.utils.strpack  
module, 453

pylablib.core.utils.units  
module, 454

pylablib.devices  
module, 1034

pylablib.devices.Agilent  
module, 507

pylablib.devices.Agilent.base  
module, 505

pylablib.devices.Agilent.pressure  
module, 505

pylablib.devices.AlliedVision  
module, 522

pylablib.devices.AlliedVision.Bonito  
module, 507

pylablib.devices.Andor  
module, 550

pylablib.devices.Andor.AndorSDK2  
module, 522

pylablib.devices.Andor.AndorSDK3  
module, 534

pylablib.devices.Andor.atcore\_features  
module, 549

pylablib.devices.Andor.base  
module, 549

pylablib.devices.Andor.Shamrock  
module, 544

`pylablib.devices.Arcus`  
    module, [563](#)

`pylablib.devices.Arcus.base`  
    module, [550](#)

`pylablib.devices.Arcus.performax`  
    module, [551](#)

`pylablib.devices.Arduino`  
    module, [566](#)

`pylablib.devices.Arduino.base`  
    module, [563](#)

`pylablib.devices.Attocube`  
    module, [574](#)

`pylablib.devices.Attocube.anc300`  
    module, [566](#)

`pylablib.devices.Attocube.anc350`  
    module, [570](#)

`pylablib.devices.Attocube.base`  
    module, [574](#)

`pylablib.devices.AWG`  
    module, [505](#)

`pylablib.devices.AWG.generic`  
    module, [455](#)

`pylablib.devices.AWG.specific`  
    module, [462](#)

`pylablib.devices.Basler`  
    module, [584](#)

`pylablib.devices.Basler.pylon`  
    module, [574](#)

`pylablib.devices.BitFlow`  
    module, [597](#)

`pylablib.devices.BitFlow.BitFlow`  
    module, [584](#)

`pylablib.devices.Conrad`  
    module, [599](#)

`pylablib.devices.Conrad.base`  
    module, [597](#)

`pylablib.devices.Cryocon`  
    module, [604](#)

`pylablib.devices.Cryocon.base`  
    module, [599](#)

`pylablib.devices.Cryomagnetics`  
    module, [613](#)

`pylablib.devices.Cryomagnetics.base`  
    module, [604](#)

`pylablib.devices.DCAM`  
    module, [621](#)

`pylablib.devices.DCAM.DCAM`  
    module, [613](#)

`pylablib.devices.ElektroAutomatik`  
    module, [625](#)

`pylablib.devices.ElektroAutomatik.base`  
    module, [621](#)

`pylablib.devices.HighFinesse`  
    module, [629](#)

`pylablib.devices.HighFinesse.wlm`  
    module, [625](#)

`pylablib.devices.Hubner`  
    module, [633](#)

`pylablib.devices.Hubner.base`  
    module, [633](#)

`pylablib.devices.Hubner.Cobolt`  
    module, [629](#)

`pylablib.devices.IMAQ`  
    module, [648](#)

`pylablib.devices.IMAQ.IMAQ`  
    module, [633](#)

`pylablib.devices.IMAQ.niimaq_attrtypes`  
    module, [648](#)

`pylablib.devices.IMAQdx`  
    module, [663](#)

`pylablib.devices.IMAQdx.IMAQdx`  
    module, [648](#)

`pylablib.devices.interface`  
    module, [1022](#)

`pylablib.devices.interface.camera`  
    module, [989](#)

`pylablib.devices.interface.stage`  
    module, [1020](#)

`pylablib.devices.Keithley`  
    module, [671](#)

`pylablib.devices.Keithley.base`  
    module, [665](#)

`pylablib.devices.Keithley.multimeter`  
    module, [666](#)

`pylablib.devices.KJL`  
    module, [665](#)

`pylablib.devices.KJL.base`  
    module, [663](#)

`pylablib.devices.Lakeshore`  
    module, [682](#)

`pylablib.devices.Lakeshore.base`  
    module, [671](#)

`pylablib.devices.LaserQuantum`  
    module, [685](#)

`pylablib.devices.LaserQuantum.base`  
    module, [682](#)

`pylablib.devices.Leybold`  
    module, [689](#)

`pylablib.devices.Leybold.base`  
    module, [685](#)

`pylablib.devices.LighthousePhotonics`  
    module, [692](#)

`pylablib.devices.LighthousePhotonics.base`  
    module, [689](#)

`pylablib.devices.Lumel`  
    module, [695](#)

`pylablib.devices.Lumel.base`  
    module, [692](#)

pylablib.devices.M2  
module, 707

pylablib.devices.M2.base  
module, 695

pylablib.devices.M2.emm  
module, 697

pylablib.devices.M2.solstis  
module, 701

pylablib.devices.Mightex  
module, 714

pylablib.devices.Mightex.base  
module, 714

pylablib.devices.Mightex.MightexSSeries  
module, 707

pylablib.devices.Modbus  
module, 717

pylablib.devices.Modbus.modbus  
module, 714

pylablib.devices.Newport  
module, 739

pylablib.devices.Newport.base  
module, 735

pylablib.devices.Newport.picomotor  
module, 736

pylablib.devices.NI  
module, 725

pylablib.devices.NI.daq  
module, 717

pylablib.devices.NKT  
module, 735

pylablib.devices.NKT.interbus  
module, 725

pylablib.devices.Omron  
module, 749

pylablib.devices.Omron.base  
module, 746

pylablib.devices.Ophir  
module, 754

pylablib.devices.Ophir.base  
module, 749

pylablib.devices.OZOptics  
module, 746

pylablib.devices.OZOptics.base  
module, 739

pylablib.devices.PCO  
module, 763

pylablib.devices.PCO.SC2  
module, 754

pylablib.devices.Pfeiffer  
module, 769

pylablib.devices.Pfeiffer.base  
module, 763

pylablib.devices.Photometrics  
module, 779

pylablib.devices.Photometrics.pvcam  
module, 769

pylablib.devices.PhotonFocus  
module, 813

pylablib.devices.PhotonFocus.PhotonFocus  
module, 779

pylablib.devices.PhysikInstrumente  
module, 824

pylablib.devices.PhysikInstrumente.base  
module, 813

pylablib.devices.PrincetonInstruments  
module, 833

pylablib.devices.PrincetonInstruments.picam  
module, 824

pylablib.devices.Rigol  
module, 838

pylablib.devices.Rigol.base  
module, 833

pylablib.devices.Rigol.power\_supply  
module, 834

pylablib.devices.SiliconSoftware  
module, 855

pylablib.devices.SiliconSoftware.fgrab  
module, 838

pylablib.devices.Sirah  
module, 868

pylablib.devices.Sirah.base  
module, 864

pylablib.devices.Sirah.Matisse  
module, 855

pylablib.devices.Sirah.tuner  
module, 864

pylablib.devices.SmarAct  
module, 876

pylablib.devices.SmarAct.base  
module, 873

pylablib.devices.SmarAct.MCS2  
module, 868

pylablib.devices.SmarAct.scu3d  
module, 873

pylablib.devices.Standa  
module, 880

pylablib.devices.Standa.base  
module, 876

pylablib.devices.Tektronix  
module, 902

pylablib.devices.Tektronix.base  
module, 880

pylablib.devices.Thorlabs  
module, 968

pylablib.devices.Thorlabs.base  
module, 911

pylablib.devices.Thorlabs.elliptec  
module, 911

pylablib.devices.Thorlabs.kinesis  
     module, 916  
 pylablib.devices.Thorlabs.misc  
     module, 945  
 pylablib.devices.Thorlabs.serial  
     module, 954  
 pylablib.devices.Thorlabs.TLCamera  
     module, 902  
 pylablib.devices.Toptica  
     module, 971  
 pylablib.devices.Toptica.base  
     module, 968  
 pylablib.devices.Toptica.ibeam  
     module, 968  
 pylablib.devices.Trinamic  
     module, 980  
 pylablib.devices.Trinamic.base  
     module, 971  
 pylablib.devices.uc480  
     module, 1031  
 pylablib.devices.uc480.uc480  
     module, 1022  
 pylablib.devices.utils  
     module, 1034  
 pylablib.devices.utils.color  
     module, 1031  
 pylablib.devices.utils.load\_lib  
     module, 1032  
 pylablib.devices.Voltcraft  
     module, 987  
 pylablib.devices.Voltcraft.base  
     module, 980  
 pylablib.devices.Voltcraft.multimeter  
     module, 981  
 pylablib.devices.Windows  
     module, 989  
 pylablib.devices.Windows.joystick  
     module, 987  
 pylablib.widgets  
     module, 1034  
 PyUSBDeviceBackend (class in  
     pylablib.core.devio.comm\_backend), 183

## Q

QCallResultSynchronizer (class in  
     pylablib.core.thread.callsync), 330  
 QContainer (class in  
     pylablib.core.gui.widgets.container), 238  
 QDialogContainer (class in  
     pylablib.core.gui.widgets.container), 255  
 QDirectCallScheduler (class in  
     pylablib.core.thread.callsync), 333  
 QDirectResultSynchronizer (class in  
     pylablib.core.thread.callsync), 331  
 QDummyResultSynchronizer (class in  
     pylablib.core.thread.callsync), 331  
 QFrameContainer (class in  
     pylablib.core.gui.widgets.container), 250  
 QGroupBoxContainer (class in  
     pylablib.core.gui.widgets.container), 259  
 QLayoutManagedWidget (class in  
     pylablib.core.gui.widgets.layout\_manager),  
     282  
 QLockNotifier (class in  
     pylablib.core.thread.synchronizing), 368  
 QMulticastThreadCallScheduler (class in  
     pylablib.core.thread.callsync), 340  
 QMultiQueueScheduler (class in  
     pylablib.core.thread.callsync), 339  
 QMultiThreadNotifier (class in  
     pylablib.core.thread.synchronizing), 368  
 QQueueLengthLimitScheduler (class in  
     pylablib.core.thread.callsync), 336  
 QQueueScheduler (class in  
     pylablib.core.thread.callsync), 334  
 QQueueSizeLimitScheduler (class in  
     pylablib.core.thread.callsync), 337  
 QScheduledCall (class in  
     pylablib.core.thread.callsync), 332  
 QScheduledCall.Callback (class in  
     pylablib.core.thread.callsync), 332  
 QScheduler (class in pylablib.core.thread.callsync), 333  
 QScrollAreaContainer (class in  
     pylablib.core.gui.widgets.container), 264  
 QScrollAreaContainer.QContainedWidget (class in  
     pylablib.core.gui.widgets.container), 264  
 QTabContainer (class in  
     pylablib.core.gui.widgets.container), 271  
 QTaskThread (class in pylablib.core.thread.controller),  
     350  
 QTaskThread.CommandAccess (class in  
     pylablib.core.thread.controller), 356  
 QTaskThread.Job (class in  
     pylablib.core.thread.controller), 351  
 QTaskThread.TBatchJob (class in  
     pylablib.core.thread.controller), 351  
 QTaskThread.TCommand (class in  
     pylablib.core.thread.controller), 351  
 QThreadCallScheduler (class in  
     pylablib.core.thread.callsync), 339  
 QThreadController (class in  
     pylablib.core.thread.controller), 342  
 QThreadControllerThread (class in  
     pylablib.core.thread.controller), 341  
 QThreadNotifier (class in  
     pylablib.core.thread.synchronizing), 367  
 query() (pylablib.devices.Agilent.pressure.XGS600  
     method), 505



`query()` (`pylablib.devices.Arcus.performax.GenericPerformaxStage` method), 913  
`method`), 551  
`query()` (`pylablib.devices.Arcus.performax.Performax2EXStage` method), 917  
`method`), 559  
`query()` (`pylablib.devices.Arcus.performax.Performax4EXStage` method), 923  
`method`), 556  
`query()` (`pylablib.devices.Arcus.performax.PerformaxDMXJSASTagemethod`), 933  
`method`), 563  
`query()` (`pylablib.devices.Arduino.base.IArduinoDevice` method), 564  
`method`), 566  
`query()` (`pylablib.devices.Attocube.anc300.ANC300` method), 566  
`method`), 598  
`query()` (`pylablib.devices.Conrad.base.RelayBoard` method), 598  
`method`), 623  
`query()` (`pylablib.devices.ElektroAutomatik.base.PS2000B` method), 623  
`method`), 630  
`query()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 630  
`method`), 663  
`query()` (`pylablib.devices.KJL.base.KJL300` method), 663  
`method`), 683  
`query()` (`pylablib.devices.LaserQuantum.base.Finesse` method), 683  
`method`), 690  
`query()` (`pylablib.devices.LighthousePhotonics.base.SproutG` method), 690  
`method`), 696  
`query()` (`pylablib.devices.M2.base.ICEBlocDevice` method), 696  
`method`), 700  
`query()` (`pylablib.devices.M2.emm.EMM` method), 700  
`method`), 706  
`query()` (`pylablib.devices.M2.solstis.Solstis` method), 706  
`method`), 736  
`query()` (`pylablib.devices.Newport.picomotor.Picomotor8742` method), 736  
`method`), 749  
`query()` (`pylablib.devices.Ophir.base.OphirDevice` method), 749  
`method`), 754  
`query()` (`pylablib.devices.Ophir.base.VegaPowerMeter` method), 754  
`method`), 744  
`query()` (`pylablib.devices.OZOptics.base.DD100` method), 744  
`method`), 744  
`query()` (`pylablib.devices.OZOptics.base.EPC04` method), 744  
`method`), 740  
`query()` (`pylablib.devices.OZOptics.base.OZOpticsDevice` method), 740  
`method`), 742  
`query()` (`pylablib.devices.OZOptics.base.TF100` method), 742  
`method`), 767  
`query()` (`pylablib.devices.Pfeiffer.base.DPG202` method), 767  
`method`), 764  
`query()` (`pylablib.devices.Pfeiffer.base.TPG260` method), 764  
`method`), 814  
`query()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` method), 814  
`method`), 818  
`query()` (`pylablib.devices.PhysikInstrumente.base.PIE516` method), 818  
`method`), 878  
`query()` (`pylablib.devices.Standa.base.Standa8SMC` method), 878  
`method`), 913  
`query()` (`pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice` method), 913  
`method`), 917  
`query()` (`pylablib.devices.Thorlabs.kinesis.KinesisDevice` method), 917  
`method`), 933  
`query()` (`pylablib.devices.Thorlabs.kinesis.KinesisMotor` method), 933  
`method`), 940  
`query()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoController` method), 940  
`method`), 937  
`query()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor` method), 937  
`method`), 944  
`query()` (`pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector` method), 944  
`method`), 926  
`query()` (`pylablib.devices.Thorlabs.kinesis.MFF` method), 926  
`method`), 969  
`query()` (`pylablib.devices.Toptica.ibeam.TopticaIBeam` method), 969  
`method`), 972  
`query()` (`pylablib.devices.Trinamic.base.TMCM1110` method), 972  
`method`), 978  
`query()` (`pylablib.devices.Trinamic.base.TMCMx110` method), 978  
`method`), 814  
`query_axis()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` method), 814  
`method`), 819  
`query_axis()` (`pylablib.devices.PhysikInstrumente.base.PIE516` method), 819  
`method`), 780  
`query_camera_name()` (in module `pylablib.devices.PhotonFocus.PhotonFocus`), 780  
`queue()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera.BufferManager` method), 580  
`quit_sync()` (`pylablib.core.thread.controller.QThreadControllerThread` method), 341  
`QWidgetContainer` (class in `pylablib.core.gui.widgets.container`), 245

## R

`ramp_divisor` (`pylablib.devices.Trinamic.base.TVVelocityParams` attribute), 972  
`ramp_down` (`pylablib.devices.Thorlabs.elliptec.TMotorInfo` attribute), 912  
`ramp_enabled` (`pylablib.devices.Standa.base.TPowerParams` attribute), 877  
`ramp_time` (`pylablib.devices.Standa.base.TPowerParams` attribute), 877  
`ramp_up` (`pylablib.devices.Thorlabs.elliptec.TMotorInfo` attribute), 912  
`Range` (class in `pylablib.core.dataproc.utils`), 163  
`RangeParameterClass` (class in `pylablib.core.devio.interface`), 198  
`ranges` (`pylablib.devices.Ophir.base.TRangeInfo` attribute), 751  
`rate` (`pylablib.devices.NI.daq.TVoltageOutputClockParameters` attribute), 718

`rate` (`pylablib.devices.Sirah.Matisse.TPiezoetDriveParameters` attribute), 855  
`read` (`pylablib.core.devio.comm_backend.FT232DeviceBackend` method), 179  
`read` (`pylablib.core.devio.comm_backend.HIDDeviceBackend` method), 187  
`read` (`pylablib.core.devio.comm_backend.IDeviceCommBackend` method), 172  
`read` (`pylablib.core.devio.comm_backend.NetworkDeviceBackend` method), 182  
`read` (`pylablib.core.devio.comm_backend.PyUSBDeviceBackend` method), 185  
`read` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` method), 190  
`read` (`pylablib.core.devio.comm_backend.SerialDeviceBackend` method), 176  
`read` (`pylablib.core.devio.comm_backend.VisaDeviceBackend` method), 174  
`read` (`pylablib.core.devio.hid.HIDDevice` method), 195  
`read` (`pylablib.core.devio.hid.HIDDevice.Reader` method), 195  
`read` (`pylablib.core.devio.SCPI.SCPIDevice` method), 167  
`read` (`pylablib.core.fileio.loadfile.BinaryTableInputFileFormatter` method), 212  
`read` (`pylablib.core.fileio.loadfile.CSVTableInputFileFormat` method), 211  
`read` (`pylablib.core.fileio.loadfile.DictionaryInputFileFormat` method), 212  
`read` (`pylablib.core.fileio.loadfile.IInputFileFormat` method), 210  
`read` (`pylablib.core.fileio.loadfile.ITextInputFileFormat` method), 211  
`read` (`pylablib.devices.AWG.generic.GenericAWG` method), 460  
`read` (`pylablib.devices.AWG.specific.Agilent33220A` method), 471  
`read` (`pylablib.devices.AWG.specific.Agilent33500` method), 465  
`read` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 483  
`read` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 477  
`read` (`pylablib.devices.AWG.specific.RigolDG1000` method), 502  
`read` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 489  
`read` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 496  
`read` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 602  
`read` (`pylablib.devices.Cryomagnetics.base.LM500` method), 607  
`read` (`pylablib.devices.Cryomagnetics.base.LM510` method), 610  
`read` (`pylablib.devices.Keithley.multimeter.Keithley2110` method), 669  
`read` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 675  
`read` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 680  
`read` (`pylablib.devices.NI.daq.NIDAQ` method), 721  
`read` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 822  
`read` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 836  
`read` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 862  
`read` (`pylablib.devices.Tektronix.base.DPO2000` method), 898  
`read` (`pylablib.devices.Tektronix.base.ITektronixScope` method), 886  
`read` (`pylablib.devices.Tektronix.base.TDS2000` method), 891  
`read` (`pylablib.devices.Thorlabs.misc.GenericPM` method), 948  
`read` (`pylablib.devices.Thorlabs.misc.PM160` method), 952  
`read` (`pylablib.devices.Thorlabs.serial.FW` method), 959  
`read` (`pylablib.devices.Thorlabs.serial.FWv1` method), 963  
`read` (`pylablib.devices.Thorlabs.serial.MDT69xA` method), 966  
`read` (`pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface` method), 956  
`read` (`pylablib.devices.Voltcraft.multimeter.VC7055` method), 983  
`read_binary_array_data` (`pylablib.core.devio.SCPI.SCPIDevice` method), 169  
`read_binary_array_data` (`pylablib.devices.AWG.generic.GenericAWG` method), 460  
`read_binary_array_data` (`pylablib.devices.AWG.specific.Agilent33220A` method), 471  
`read_binary_array_data` (`pylablib.devices.AWG.specific.Agilent33500` method), 465  
`read_binary_array_data` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 483  
`read_binary_array_data` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 477  
`read_binary_array_data` (`pylablib.devices.AWG.specific.RigolDG1000` method), 502  
`read_binary_array_data` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 489  
`read_binary_array_data` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 496  
`read_binary_array_data` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 477  
`read_binary_array_data` (`pylablib.devices.AWG.specific.RigolDG1000` method), 502



- method*), 502
- `read_binary_array_data()` (*py-lablib.devices.AWG.specific.RSInstekAFG21000* *method*), 490
- `read_binary_array_data()` (*py-lablib.devices.AWG.specific.TektronixAFG1000* *method*), 496
- `read_binary_array_data()` (*py-lablib.devices.Cryocon.base.Cryocon1x* *method*), 602
- `read_binary_array_data()` (*py-lablib.devices.Cryomagnetics.base.LM500* *method*), 607
- `read_binary_array_data()` (*py-lablib.devices.Cryomagnetics.base.LM510* *method*), 611
- `read_binary_array_data()` (*py-lablib.devices.Keithley.multimeter.Keithley2110* *method*), 669
- `read_binary_array_data()` (*py-lablib.devices.Lakeshore.base.Lakeshore218* *method*), 675
- `read_binary_array_data()` (*py-lablib.devices.Lakeshore.base.Lakeshore370* *method*), 680
- `read_binary_array_data()` (*py-lablib.devices.PhysikInstrumente.base.PIE515* *method*), 822
- `read_binary_array_data()` (*py-lablib.devices.Rigol.power\_supply.DP1116A* *method*), 837
- `read_binary_array_data()` (*py-lablib.devices.Sirah.Matisse.SirahMatisse* *method*), 862
- `read_binary_array_data()` (*py-lablib.devices.Tektronix.base.DPO2000* *method*), 898
- `read_binary_array_data()` (*py-lablib.devices.Tektronix.base.ITektronixScope* *method*), 886
- `read_binary_array_data()` (*py-lablib.devices.Tektronix.base.TDS2000* *method*), 891
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.misc.GenericPM* *method*), 948
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.misc.PM160* *method*), 952
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.serial.FW* *method*), 959
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.serial.FWv1* *method*), 963
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.serial.MDT69xA* *method*), 966
- `read_binary_array_data()` (*py-lablib.devices.Thorlabs.serial.ThorlabsSerialInterface* *method*), 956
- `read_binary_array_data()` (*py-lablib.devices.Voltcraft.multimeter.VC7055* *method*), 983
- `read_columns()` (*in module py-lablib.core.fileio.parse\_csv*), 223
- `read_dict_and_comments()` (*in module py-lablib.core.fileio.loadfile\_utils*), 216
- `read_directly` (*pylablib.devices.PrincetonInstruments.picam.PicamAttribute* *attribute*), 825
- `read_in_aux_port()` (*py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera* *method*), 526
- `read_message()` (*pylablib.devices.Voltcraft.multimeter.VC880* *method*), 985
- `read_multichar_term()` (*py-lablib.core.devio.comm\_backend.FT232DeviceBackend* *method*), 179
- `read_multichar_term()` (*py-lablib.core.devio.comm\_backend.HIDeviceBackend* *method*), 187
- `read_multichar_term()` (*py-lablib.core.devio.comm\_backend.NetworkDeviceBackend* *method*), 182
- `read_multichar_term()` (*py-lablib.core.devio.comm\_backend.PyUSBDeviceBackend* *method*), 185
- `read_multichar_term()` (*py-lablib.core.devio.comm\_backend.SerialDeviceBackend* *method*), 176
- `read_multiple_images()` (*py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera* *method*), 518
- `read_multiple_images()` (*py-lablib.devices.AlliedVision.Bonito.IBonitoCamera* *method*), 512
- `read_multiple_images()` (*py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera* *method*), 532
- `read_multiple_images()` (*py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera* *method*), 543
- `read_multiple_images()` (*py-lablib.devices.Basler.pylon.BaslerPylonCamera* *method*), 583
- `read_multiple_images()` (*py-lablib.devices.BitFlow.BitFlow.BitFlowCamera* *method*), 594

<code>read_multiple_images()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 589	(py- <code>read_multiple_images()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 802	(py-
<code>read_multiple_images()</code> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 621	(py- <code>read_multiple_images()</code> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 833	(py-
<code>read_multiple_images()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 645	(py- <code>read_multiple_images()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 852	(py-
<code>read_multiple_images()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 639	(py- <code>read_multiple_images()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method</i> ), 846	(py-
<code>read_multiple_images()</code> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 660	(py- <code>read_multiple_images()</code> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 907	(py-
<code>read_multiple_images()</code> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 655	(py- <code>read_multiple_images()</code> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1031	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 999	(py- <code>read_multiple_sweeps()</code> <i>lablib.devices.Tektronix.base.DPO2000</i> <i>method</i> ), 899	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1017	(py- <code>read_multiple_sweeps()</code> <i>lablib.devices.Tektronix.base.ITektronixScope</i> <i>method</i> ), 884	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 992	(py- <code>read_multiple_sweeps()</code> <i>lablib.devices.Tektronix.base.TDS2000</i> <i>method</i> ), 892	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1008	(py- <code>read_newest_image()</code> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 518	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1004	(py- <code>read_newest_image()</code> <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 512	(py-
<code>read_multiple_images()</code> <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1013	(py- <code>read_newest_image()</code> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 532	(py-
<code>read_multiple_images()</code> <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 712	(py- <code>read_newest_image()</code> <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 542	(py-
<code>read_multiple_images()</code> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 761	(py- <code>read_newest_image()</code> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 583	(py-
<code>read_multiple_images()</code> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 775	(py- <code>read_newest_image()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 594	(py-
<code>read_multiple_images()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 786	(py- <code>read_newest_image()</code> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 589	(py-
<code>read_multiple_images()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowGrabber</i> <i>method</i> ), 810	(py- <code>read_newest_image()</code> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 620	(py-
<code>read_multiple_images()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> <i>method</i> ), 793	(py- <code>read_newest_image()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 645	(py-

<code>read_newest_image()</code> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 640	(py- <i>read_newest_image()</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> <i>method</i> ), 846	(py-
<code>read_newest_image()</code> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 660	(py- <i>read_newest_image()</i> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 909	(py-
<code>read_newest_image()</code> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 655	(py- <i>read_newest_image()</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1030	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 999	(py- <i>read_oldest_image()</i> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> <i>method</i> ), 518	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1018	(py- <i>read_oldest_image()</i> <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> <i>method</i> ), 512	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 993	(py- <i>read_oldest_image()</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> <i>method</i> ), 532	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.IExposureCamera</i> <i>method</i> ), 1008	(py- <i>read_oldest_image()</i> <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 542	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> <i>method</i> ), 1004	(py- <i>read_oldest_image()</i> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 583	(py-
<code>read_newest_image()</code> <i>lablib.devices.interface.camera.IROICamera</i> <i>method</i> ), 1013	(py- <i>read_oldest_image()</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> <i>method</i> ), 594	(py-
<code>read_newest_image()</code> <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> <i>method</i> ), 712	(py- <i>read_oldest_image()</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> <i>method</i> ), 590	(py-
<code>read_newest_image()</code> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 761	(py- <i>read_oldest_image()</i> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> <i>method</i> ), 620	(py-
<code>read_newest_image()</code> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> <i>method</i> ), 777	(py- <i>read_oldest_image()</i> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> <i>method</i> ), 645	(py-
<code>read_newest_image()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 786	(py- <i>read_oldest_image()</i> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> <i>method</i> ), 640	(py-
<code>read_newest_image()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> <i>method</i> ), 810	(py- <i>read_oldest_image()</i> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> <i>method</i> ), 661	(py-
<code>read_newest_image()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> <i>method</i> ), 793	(py- <i>read_oldest_image()</i> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> <i>method</i> ), 655	(py-
<code>read_newest_image()</code> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 802	(py- <i>read_oldest_image()</i> <i>lablib.devices.interface.camera.IAttributeCamera</i> <i>method</i> ), 999	(py-
<code>read_newest_image()</code> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> <i>method</i> ), 832	(py- <i>read_oldest_image()</i> <i>lablib.devices.interface.camera.IBinROICamera</i> <i>method</i> ), 1018	(py-
<code>read_newest_image()</code> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> <i>method</i> ), 852	(py- <i>read_oldest_image()</i> <i>lablib.devices.interface.camera.ICamera</i> <i>method</i> ), 993	(py-

`read_oldest_image()` (py-lablib.devices.interface.camera.IExposureCamera method), 1008  
`read_oldest_image()` (py-lablib.devices.interface.camera.IGrabberAttributeCamera method), 1004  
`read_oldest_image()` (py-lablib.devices.interface.camera.IROICamera method), 1013  
`read_oldest_image()` (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 713  
`read_oldest_image()` (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 762  
`read_oldest_image()` (py-lablib.devices.Photometrics.pvcam.PvcamCamera method), 777  
`read_oldest_image()` (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 786  
`read_oldest_image()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera method), 810  
`read_oldest_image()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 793  
`read_oldest_image()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusPFCamera method), 803  
`read_oldest_image()` (py-lablib.devices.PrincetonInstruments.picam.PicamCamera method), 832  
`read_oldest_image()` (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 852  
`read_oldest_image()` (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 847  
`read_oldest_image()` (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 909  
`read_oldest_image()` (py-lablib.devices.uc480.uc480.UC480Camera method), 1030  
`read_raw_data()` (py-lablib.devices.Tektronix.base.DPO2000 method), 899  
`read_raw_data()` (py-lablib.devices.Tektronix.base.ITektronixScope method), 884  
`read_raw_data()` (py-lablib.devices.Tektronix.base.TDS2000 method), 892  
`read_sweep()` (py-lablib.devices.Tektronix.base.DPO2000 method), 899  
`read_sweep()` (py-lablib.devices.Tektronix.base.ITektronixScope method), 885  
`read_sweep()` (py-lablib.devices.Tektronix.base.TDS2000 method), 892  
`read_table()` (in module py-lablib.core.fileio.parse\_csv), 224  
`read_trigger()` (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 518  
`read_trigger()` (py-lablib.devices.IMAQ.IMAQ.IMAQCamera method), 645  
`read_trigger()` (py-lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 636  
`read_trigger()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera method), 794  
`readable` (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute), 535  
`readable` (py-lablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576  
`readable` (py-lablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614  
`readable` (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649  
`readable` (py-lablib.devices.Photometrics.pvcam.PvcamAttribute attribute), 770  
`readable` (py-lablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute), 780  
`ReadChangeLock` (class in py-lablib.core.thread.utils), 371  
`reading()` (py-lablib.core.thread.utils.ReadChangeLock method), 371  
`readline()` (py-lablib.core.devio.comm\_backend.FT232DeviceBackend method), 179  
`readline()` (py-lablib.core.devio.comm\_backend.HIDeviceBackend method), 187  
`readline()` (py-lablib.core.devio.comm\_backend.IDeviceCommBackend method), 172  
`readline()` (py-lablib.core.devio.comm\_backend.NetworkDeviceBackend method), 182  
`readline()` (py-lablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 184  
`readline()` (py-lablib.core.devio.comm\_backend.RecordedDeviceBackend method), 190  
`readline()` (py-lablib.core.devio.comm\_backend.SerialDeviceBackend method), 176  
`readline()` (py-lablib.core.devio.comm\_backend.VisaDeviceBackend method), 174  
`readlines()` (py-lablib.core.devio.comm\_backend.FT232DeviceBackend method), 180  
`readlines()` (py-lablib.core.devio.comm\_backend.HIDeviceBackend method), 188  
`readlines()` (py-lablib.core.devio.comm\_backend.IDeviceCommBackend method), 172



`readlines()` (pylablib.core.devio.comm\_backend.NetworkDeviceBackend method), 183  
`readlines()` (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 186  
`readlines()` (pylablib.core.devio.comm\_backend.RecordedDeviceBackend method), 191  
`readlines()` (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 177  
`readlines()` (pylablib.core.devio.comm\_backend.VisaDeviceBackend method), 174  
`readn()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3ConnectionManager method), 539  
`reason` (pylablib.devices.Attocube.anc350.ANC350.Reply attribute), 570  
`reboot()` (pylablib.devices.PCO.SC2.PCOSC2Camera method), 755  
`reboot()` (pylablib.devices.Toptica.ibeam.TopticaIBeam method), 969  
`reconnect()` (pylablib.core.devio.SCPI.SCPIDevice method), 166  
`reconnect()` (pylablib.devices.AWG.generic.GenericAWGRecordedDeviceBackend method), 460  
`reconnect()` (pylablib.devices.AWG.specific.Agilent33220A.rectangle\_k() (in module pylablib.core.dataproc.specfunc), 151  
`reconnect()` (pylablib.devices.AWG.specific.Agilent33500.rectangle\_w() (in module pylablib.core.dataproc.specfunc), 151  
`reconnect()` (pylablib.devices.AWG.specific.InstekAFG2000.rectangle\_w\_ft() (in module pylablib.core.dataproc.specfunc), 152  
`reconnect()` (pylablib.devices.AWG.specific.InstekAFG2225.recursive\_map() (in module pylablib.core.utils.general), 425  
`reconnect()` (pylablib.devices.AWG.specific.RigolDG1000.recv() (pylablib.core.utils.ipc.IIPCCChannel method), 435  
`reconnect()` (pylablib.devices.AWG.specific.RSInstekAFG2400() (pylablib.core.utils.ipc.PipeIPCCChannel method), 435  
`reconnect()` (pylablib.devices.AWG.specific.TektronixAFG4000() (pylablib.core.utils.ipc.SharedMemIPCCChannel method), 436  
`reconnect()` (pylablib.devices.Cryocon.base.CryoconIx.recv() (pylablib.core.utils.net.ClientSocket method), 442  
`reconnect()` (pylablib.devices.Cryomagnetics.base.LM500.recv\_ack() (pylablib.core.utils.net.ClientSocket method), 443  
`reconnect()` (pylablib.devices.Cryomagnetics.base.LM510.recv\_all() (pylablib.core.utils.net.ClientSocket method), 443  
`reconnect()` (pylablib.devices.Keithley.multimeter.Keithley2400.recv\_comm() (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913  
`reconnect()` (pylablib.devices.Lakeshore.base.Lakeshore218recv\_comm() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 917  
`reconnect()` (pylablib.devices.Lakeshore.base.Lakeshore370recv\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 923  
`reconnect()` (pylablib.devices.PhysikInstrumente.base.PIE515recv\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 933  
`reconnect()` (pylablib.devices.Rigol.power\_supply.DP1116recv\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 941  
`reconnect()` (pylablib.devices.Sirah.Matisse.SirahMatisserrecv\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 937

[recv\\_comm\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisQuadDetectomethod*), 552  
[recv\\_comm\(\)](#) (*pylablib.devices.Thorlabs.kinesis.MFFmethod*), 945  
[recv\\_comm\(\)](#) (*pylablib.devices.Thorlabs.kinesis.MFFmethod*), 927  
[recv\\_decllen\(\)](#) (*pylablib.core.utils.net.ClientSocketmethod*), 442  
[recv\\_delimiter\(\)](#) (*pylablib.core.utils.net.ClientSocketmethod*), 442  
[recv\\_fixedlen\(\)](#) (*pylablib.core.utils.net.ClientSocketmethod*), 442  
[recv\\_JSON\(\)](#) (*in module pylablib.core.utils.net*), 443  
[recv\\_numpy\(\)](#) (*pylablib.core.utils.ipc.IIPChannelmethod*), 435  
[recv\\_numpy\(\)](#) (*pylablib.core.utils.ipc.PipeIPChannelmethod*), 435  
[recv\\_numpy\(\)](#) (*pylablib.core.utils.ipc.SharedMemIPChannelmethod*), 436  
[reduct\\_delay](#) (*pylablib.devices.Standa.base.TPowerParameterattribute*), 878  
[reduct\\_enabled](#) (*pylablib.devices.Standa.base.TPowerParameterattribute*), 878  
[refresh\\_acquisition\(\)](#) (*pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method*), 661  
[refresh\\_acquisition\(\)](#) (*pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method*), 653  
[register\(\)](#) (*pylablib.devices.Basler.pylon.BaslerPylonCamera method*), 579  
[register\(\)](#) (*pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method*), 657  
[register\(\)](#) (*pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method*), 652  
[regular\\_grid\\_from\\_scatter\(\)](#) (*in module pylablib.core.dataproc.interpolate*), 149  
[relative\\_path\(\)](#) (*in module pylablib.core.utils.files*), 413  
[RelayBoard](#) (*class in pylablib.devices.Conrad.base*), 597  
[RelayBoard.TMessage](#) (*class in pylablib.devices.Conrad.base*), 598  
[release\(\)](#) (*pylablib.core.thread.synchronizing.QLockNotifier method*), 368  
[relevant](#) (*pylablib.devices.PrincetonInstruments.picam.PicamAttribute*), 825  
[reload\\_all\(\)](#) (*in module pylablib*), 1034  
[reload\\_package\\_modules\(\)](#) (*in module pylablib.core.utils.module*), 438  
[rem\(\)](#) (*pylablib.core.utils.functions.AttrObjectProperty method*), 424  
[rem\(\)](#) (*pylablib.core.utils.functions.IObjectProperty method*), 423  
[rem\(\)](#) (*pylablib.core.utils.functions.MethodObjectProperty method*), 424  
[remap\\_axes\(\)](#) (*pylablib.devices.Arcus.performax.GenericPerformaxStage method*), 552  
[remap\\_axes\(\)](#) (*pylablib.devices.Arcus.performax.Performax2EXStage method*), 559  
[remap\\_axes\(\)](#) (*pylablib.devices.Arcus.performax.Performax4EXStage method*), 556  
[remap\\_axes\(\)](#) (*pylablib.devices.Arcus.performax.PerformaxDMXJSStage method*), 563  
[remap\\_axes\(\)](#) (*pylablib.devices.Attocube.anc300.ANC300 method*), 569  
[remap\\_axes\(\)](#) (*pylablib.devices.Attocube.anc350.ANC350 method*), 573  
[remap\\_axes\(\)](#) (*pylablib.devices.interface.stage.IMultiAxisStage method*), 1021  
[remap\\_axes\(\)](#) (*pylablib.devices.Newport.picomotor.Picomotor8742 method*), 739  
[remap\\_axes\(\)](#) (*pylablib.devices.PhysikInstrumente.base.GenericPIController method*), 816  
[remap\\_axes\(\)](#) (*pylablib.devices.PhysikInstrumente.base.PIE515 method*), 822  
[remap\\_axes\(\)](#) (*pylablib.devices.PhysikInstrumente.base.PIE516 method*), 819  
[remap\\_axes\(\)](#) (*pylablib.devices.SmarAct.MCS2.MCS2 method*), 873  
[remap\\_axes\(\)](#) (*pylablib.devices.SmarAct.scu3d.SCU3D method*), 876  
[remap\\_axes\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisDevice method*), 923  
[remap\\_buffer\\_size\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisMotor method*), 934  
[remap\\_buffers\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisMotor method*), 941  
[remap\\_buffers\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method*), 938  
[remap\\_buffers\(\)](#) (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method*), 938  
[remap\\_axes\(\)](#) (*pylablib.devices.Thorlabs.kinesis.MFF method*), 927  
[remap\\_axes\(\)](#) (*pylablib.devices.Trinamic.base.TMCMx110 method*), 978  
[remote\\_call\(\)](#) (*in module pylablib.core.thread.controller*), 341  
[remove\\_batch\\_job\(\)](#) (*pylablib.core.thread.controller.QTaskThread method*), 352  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.IQContainer method*), 237  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.IQWidgetContainer method*), 241  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.QContainer method*), 240  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.QDialogContainer method*), 258  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.QFrameContainer method*), 253  
[remove\\_child\(\)](#) (*pylablib.core.gui.widgets.container.QGroupBoxContainer method*), 263

`remove_child()` (pylablib.core.gui.widgets.container.QScrollAreaContainer), 305  
`remove_child()` (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainerWidgetBackend), 172  
`remove_child()` (pylablib.core.gui.widgets.container.QTabContainer), 274  
`remove_child()` (pylablib.core.gui.widgets.container.QWidgetContainer), 249  
`remove_child()` (pylablib.core.gui.widgets.param\_table.ParamTable), 292  
`remove_child()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_dir()` (in module pylablib.core.utils.files), 414  
`remove_dir_if_empty()` (in module pylablib.core.utils.files), 414  
`remove_exception_hook()` (in module pylablib.core.thread.controller), 341  
`remove_handler()` (pylablib.core.gui.value\_handling.GUIValues), 327  
`remove_indicator_handler()` (pylablib.core.gui.value\_handling.GUIValues), 328  
`remove_job()` (pylablib.core.thread.controller.QTaskThread), 352  
`remove_layout_element()` (pylablib.core.gui.widgets.container.IQWidgetContainer), 244  
`remove_layout_element()` (pylablib.core.gui.widgets.container.QDialogContainer), 258  
`remove_layout_element()` (pylablib.core.gui.widgets.container.QFrameContainer), 253  
`remove_layout_element()` (pylablib.core.gui.widgets.container.QGroupBoxContainer), 263  
`remove_layout_element()` (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainerWidgetBackend), 172  
`remove_layout_element()` (pylablib.core.gui.widgets.container.QWidgetContainer), 249  
`remove_layout_element()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget), 280  
`remove_layout_element()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget), 283  
`remove_layout_element()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget), 283  
`remove_layout_element()` (pylablib.core.gui.widgets.param\_table.ParamTable), 294  
`remove_layout_element()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_layout_element()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_layout_element()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_longest_term()` (in module pylablib.core.utils.observer\_pool.ObserverPool), 446  
`remove_observer()` (pylablib.core.utils.observer\_pool.ObserverPool), 446  
`remove_observer()` (pylablib.core.utils.general.StreamFileLogger), 432  
`remove_shortcut()` (pylablib.core.utils.dictionary.PrefixShortcutTree), 411  
`remove_status_line()` (in module pylablib.devices.interface.camera), 1019  
`remove_status_line()` (in module pylablib.devices.PhotonFocus.PhotonFocus), 813  
`remove_stop_notifier()` (pylablib.core.thread.controller.QTaskThread), 359  
`remove_stop_notifier()` (pylablib.core.thread.controller.QThreadController), 349  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.IQWidgetContainer), 244  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.QDialogContainer), 258  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.QFrameContainer), 254  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.QGroupBoxContainer), 263  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainerWidgetBackend), 172  
`remove_sublayout_items()` (pylablib.core.gui.widgets.container.QWidgetContainer), 249  
`remove_sublayout_items()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget), 280  
`remove_sublayout_items()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget), 283  
`remove_sublayout_items()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget), 283  
`remove_sublayout_items()` (pylablib.core.gui.widgets.param\_table.ParamTable), 294  
`remove_sublayout_items()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_sublayout_items()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_sublayout_items()` (pylablib.core.gui.widgets.param\_table.StatusTable), 305  
`remove_tab()` (pylablib.core.gui.widgets.container.QTabContainer), 272

`remove_widget()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 286  
`remove_widget()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 305  
`removed` (pylablib.core.utils.dictionary.DictionaryDiff attribute), 385  
`reopen()` (pylablib.devices.Arduino.base.IArduinoDevice method), 564  
`rep` (pylablib.core.utils.string.TConversionClass attribute), 451  
`repr` (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 577  
`repr_single_value()` (pylablib.core.gui.value\_handling.CheckboxValueHandler method), 320  
`repr_single_value()` (pylablib.core.gui.value\_handling.ComboBoxValueHandler method), 323  
`repr_single_value()` (pylablib.core.gui.value\_handling.IBoolValueHandler method), 319  
`repr_single_value()` (pylablib.core.gui.value\_handling.ISingleValueHandler method), 316  
`repr_single_value()` (pylablib.core.gui.value\_handling.LabelValueHandler method), 318  
`repr_single_value()` (pylablib.core.gui.value\_handling.LineEditValueHandler method), 317  
`repr_single_value()` (pylablib.core.gui.value\_handling.ProgressBarValueHandler method), 324  
`repr_single_value()` (pylablib.core.gui.value\_handling.PushButtonValueHandler method), 321  
`repr_single_value()` (pylablib.core.gui.value\_handling.ToolButtonValueHandler method), 322  
`repr_value()` (pylablib.core.gui.value\_handling.CheckboxValueHandler method), 320  
`repr_value()` (pylablib.core.gui.value\_handling.ComboBoxValueHandler method), 323  
`repr_value()` (pylablib.core.gui.value\_handling.GUIValues attribute), 329  
`repr_value()` (pylablib.core.gui.value\_handling.IBoolValueHandler attribute), 319  
`repr_value()` (pylablib.core.gui.value\_handling.ISingleValueHandler attribute), 316  
`repr_value()` (pylablib.core.gui.value\_handling.IValueHandler attribute), 312  
`repr_value()` (pylablib.core.gui.value\_handling.LabelIndicatorHandler attribute), 499  
`repr_value()` (pylablib.core.gui.value\_handling.LabelValueHandler method), 318  
`repr_value()` (pylablib.core.gui.value\_handling.LineEditValueHandler method), 317  
`repr_value()` (pylablib.core.gui.value\_handling.ProgressBarValueHandler method), 324  
`repr_value()` (pylablib.core.gui.value\_handling.PropertyValueHandler method), 314  
`repr_value()` (pylablib.core.gui.value\_handling.PushButtonValueHandler method), 321  
`repr_value()` (pylablib.core.gui.value\_handling.StandardValueHandler method), 315  
`repr_value()` (pylablib.core.gui.value\_handling.ToolButtonValueHandler method), 322  
`repr_value()` (pylablib.core.gui.value\_handling.VirtualValueHandler method), 313  
`repr_value()` (pylablib.core.gui.widgets.button.ToggleButton method), 232  
`repr_value()` (pylablib.core.gui.widgets.button\_selector.ButtonSelector method), 234  
`repr_value()` (pylablib.core.gui.widgets.combo\_box.ComboBox method), 235  
`repr_value()` (pylablib.core.gui.widgets.edit.NumEdit method), 276  
`repr_value()` (pylablib.core.gui.widgets.label.EnumLabel method), 278  
`repr_value()` (pylablib.core.gui.widgets.label.NumLabel method), 279  
`request_stop()` (pylablib.core.thread.controller.QTaskThread method), 359  
`request_stop()` (pylablib.core.thread.controller.QThreadController method), 348  
`requires_symmetric_roi()` (pylablib.devices.PCO.SC2.PCOS2Camera method), 758  
`raise` (in module pylablib.core.devio.comm\_backend), 170  
`reraise()` (pylablib.core.utils.general.RetryOnException.ExceptionCatch attribute), 428  
`ReraiseError` (pylablib.core.devio.SCPI.SCPIDevice attribute), 166  
`ReraiseError` (pylablib.devices.AWG.generic.GenericAWG attribute), 455  
`ReraiseError` (pylablib.devices.AWG.specific.Agilent33220A attribute), 468  
`ReraiseError` (pylablib.devices.AWG.specific.Agilent33500 attribute), 462  
`ReraiseError` (pylablib.devices.AWG.specific.InstekAFG2000 attribute), 480  
`ReraiseError` (pylablib.devices.AWG.specific.InstekAFG2225 attribute), 474  
`ReraiseError` (pylablib.devices.AWG.specific.RigolDG1000 attribute), 499



[ReraiseError \(pylablib.devices.AWG.specific.RSInstekAFG21000 attribute\), 486](#)  
[ReraiseError \(pylablib.devices.AWG.specific.TektronixAFG1000 attribute\), 493](#)  
[ReraiseError \(pylablib.devices.Cryocon.base.Cryocon1x attribute\), 600](#)  
[ReraiseError \(pylablib.devices.Cryomagnetics.base.LM500 attribute\), 604](#)  
[ReraiseError \(pylablib.devices.Cryomagnetics.base.LM510 attribute\), 609](#)  
[ReraiseError \(pylablib.devices.Keithley.mmultimeter.Keithley2110 attribute\), 666](#)  
[ReraiseError \(pylablib.devices.Lakeshore.base.Lakeshore248 attribute\), 672](#)  
[ReraiseError \(pylablib.devices.Lakeshore.base.Lakeshore370 attribute\), 678](#)  
[ReraiseError \(pylablib.devices.M2.base.ICEBlocDevice attribute\), 696](#)  
[ReraiseError \(pylablib.devices.M2.emm.EMM attribute\), 699](#)  
[ReraiseError \(pylablib.devices.M2.solstis.Solstis attribute\), 706](#)  
[ReraiseError \(pylablib.devices.NI.daq.NIDAQ attribute\), 718](#)  
[ReraiseError \(pylablib.devices.PhysikInstrumente.base.PH1155 attribute\), 819](#)  
[ReraiseError \(pylablib.devices.Rigol.power\\_supply.DP1116 attribute\), 834](#)  
[ReraiseError \(pylablib.devices.Sirah.Matisse.SirahMatisse200 attribute\), 856](#)  
[ReraiseError \(pylablib.devices.Tektronix.base.DPO2000 attribute\), 895](#)  
[ReraiseError \(pylablib.devices.Tektronix.base.ITektronixScope attribute\), 881](#)  
[ReraiseError \(pylablib.devices.Tektronix.base.TDS2000 attribute\), 888](#)  
[ReraiseError \(pylablib.devices.Thorlabs.misc.GenericPM100 attribute\), 946](#)  
[ReraiseError \(pylablib.devices.Thorlabs.misc.PM160 attribute\), 950](#)  
[ReraiseError \(pylablib.devices.Thorlabs.serial.FW attribute\), 958](#)  
[ReraiseError \(pylablib.devices.Thorlabs.serial.FWv1 attribute\), 962](#)  
[ReraiseError \(pylablib.devices.Thorlabs.serial.MDT69xAres attribute\), 965](#)  
[ReraiseError \(pylablib.devices.Thorlabs.serial.ThorlabsScope attribute\), 954](#)  
[ReraiseError \(pylablib.devices.Voltcraft.mmultimeter.VC701 attribute\), 981](#)  
[res\\_range \(pylablib.devices.Lakeshore.base.TLakeshore370 attribute\), 677](#)  
[rescale\(\) \(pylablib.core.dataproc.utils.Range method\), 164](#)  
[reset\\_peak\(\) \(in module pylablib.core.dataproc.feature\), 135](#)  
[reset\(\) \(in module pylablib.core.thread.profile\), 366](#)  
[reset\(\) \(pylablib.core.dataproc.filters.RunningDebounceFilter method\), 141](#)  
[reset\(\) \(pylablib.core.dataproc.filters.RunningDecimationFilter method\), 140](#)  
[reset\(\) \(pylablib.core.devio.SCPIDevice method\), 166](#)  
[reset\(\) \(pylablib.core.utils.general.Countdown method\), 429](#)  
[reset\(\) \(pylablib.core.utils.general.Timer method\), 430](#)  
[reset\(\) \(pylablib.core.utils.general.TimeTracker method\), 431](#)  
[reset\(\) \(pylablib.core.utils.general.UIDGenerator method\), 429](#)  
[reset\(\) \(pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method\), 519](#)  
[reset\(\) \(pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera.BufferManager method\), 539](#)  
[reset\(\) \(pylablib.devices.AWG.generic.GenericAWG method\), 460](#)  
[reset\(\) \(pylablib.devices.AWG.specific.Agilent33220A method\), 471](#)  
[reset\(\) \(pylablib.devices.AWG.specific.Agilent33500 method\), 465](#)  
[reset\(\) \(pylablib.devices.AWG.specific.InstekAFG2000 method\), 484](#)  
[reset\(\) \(pylablib.devices.AWG.specific.InstekAFG2225 method\), 478](#)  
[reset\(\) \(pylablib.devices.AWG.specific.RigolDG1000 method\), 502](#)  
[reset\(\) \(pylablib.devices.AWG.specific.RSInstekAFG21000 method\), 490](#)  
[reset\(\) \(pylablib.devices.AWG.specific.TektronixAFG1000 method\), 496](#)  
[reset\(\) \(pylablib.devices.BitFlow.BitFlow.BitFlowCamera.BufferManager method\), 591](#)  
[reset\(\) \(pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.BufferManager method\), 587](#)  
[reset\(\) \(pylablib.devices.Cryocon.base.Cryocon1x method\), 602](#)  
[reset\(\) \(pylablib.devices.Cryomagnetics.base.LM500 method\), 607](#)  
[reset\(\) \(pylablib.devices.Cryomagnetics.base.LM510 method\), 611](#)  
[reset\(\) \(pylablib.devices.IMAQ.IMAQ.IMAQCamera method\), 646](#)  
[reset\(\) \(pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method\), 634](#)  
[reset\(\) \(pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method\), 661](#)  
[reset\(\) \(pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.Call method\), 657](#)

[reset\(\)](#) (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 983  
[reset\(\)](#) (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.CallbackManager method), 651  
[reset\(\)](#) (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.CallBackManager method), 652  
[reset\(\)](#) (pylablib.devices.interface.camera.FrameCounter method), 994  
[reset\(\)](#) (pylablib.devices.interface.camera.FrameNotifier method), 995  
[reset\(\)](#) (pylablib.devices.Keithley.multimeter.Keithley2110 method), 670  
[reset\(\)](#) (pylablib.devices.KJL.base.KJL300 method), 664  
[reset\(\)](#) (pylablib.devices.Lakeshore.base.Lakeshore218 method), 676  
[reset\(\)](#) (pylablib.devices.Lakeshore.base.Lakeshore370 method), 680  
[reset\(\)](#) (pylablib.devices.Newport.picomotor.Picomotor8742 method), 736  
[reset\(\)](#) (pylablib.devices.NI.daq.NIDAQ method), 718  
[reset\(\)](#) (pylablib.devices.Ophir.base.VegaPowerMeter method), 751  
[reset\(\)](#) (pylablib.devices.PCO.SC2.PCOSC2Camera.ScheduleLoop method), 756  
[reset\(\)](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 806  
[reset\(\)](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 794  
[reset\(\)](#) (pylablib.devices.PhysikInstrumente.base.PIE515 method), 822  
[reset\(\)](#) (pylablib.devices.Rigol.power\_supply.DP1116A method), 837  
[reset\(\)](#) (pylablib.devices.Sirah.Matisse.SirahMatisse method), 862  
[reset\(\)](#) (pylablib.devices.Tektronix.base.DPO2000 method), 899  
[reset\(\)](#) (pylablib.devices.Tektronix.base.ITektronixScope method), 887  
[reset\(\)](#) (pylablib.devices.Tektronix.base.TDS2000 method), 892  
[reset\(\)](#) (pylablib.devices.Thorlabs.misc.GenericPM method), 949  
[reset\(\)](#) (pylablib.devices.Thorlabs.misc.PM160 method), 953  
[reset\(\)](#) (pylablib.devices.Thorlabs.serial.FW method), 960  
[reset\(\)](#) (pylablib.devices.Thorlabs.serial.FWv1 method), 963  
[reset\(\)](#) (pylablib.devices.Thorlabs.serial.MDT69xA method), 966  
[reset\(\)](#) (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 956  
[reset\(\)](#) (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera.RingBuffer method), 904  
[reset\(\)](#) (pylablib.devices.Voltcraft.multimeter.VC7055 method), 983  
[reset\\_api\(\)](#) (in module pylablib.devices.PCO.SC2), 734  
[reset\\_board\(\)](#) (pylablib.devices.Arduino.base.IArduinoDevice method), 564  
[reset\\_error\(\)](#) (pylablib.devices.Pfeiffer.base.TPG260 method), 766  
[reset\\_filter\(\)](#) (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547  
[reset\\_flipper\(\)](#) (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547  
[reset\\_focus\\_mirror\(\)](#) (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548  
[reset\\_overflows\\_counter\(\)](#) (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 540  
[reset\\_slit\(\)](#) (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547  
[reset\\_wavelength\(\)](#) (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546  
[resize\\_buffer\(\)](#) (pylablib.devices.Keithley.multimeter.TConfigurationParameter attribute), 666  
[resolution](#) (pylablib.devices.Keithley.multimeter.TGenericFunctionParameter attribute), 666  
[restart\(\)](#) (in module pylablib.core.utils.general), 433  
[restart\(\)](#) (pylablib.devices.OZOptics.base.DD100 method), 744  
[restart\(\)](#) (pylablib.devices.OZOptics.base.OZOpticsDevice method), 740  
[restart\(\)](#) (pylablib.devices.OZOptics.base.TF100 method), 742  
[restart\\_app\(\)](#) (in module pylablib.core.thread.controller), 364  
[restart\\_autostart\(\)](#) (pylablib.devices.Hubner.Cobolt.Cobolt method), 630  
[restart\\_batch\\_job\(\)](#) (pylablib.core.thread.controller.QTaskThread method), 353  
[restart\\_lib\(\)](#) (in module pylablib.devices.Andor.AndorSDK2), 522  
[restart\\_lib\(\)](#) (in module pylablib.devices.Andor.AndorSDK3), 534  
[restart\\_lib\(\)](#) (in module pylablib.devices.Andor.Shamrock), 544  
[restart\\_lib\(\)](#) (in module pylablib.devices.Basler.pylon), 575  
[restart\\_lib\(\)](#) (in module pylablib.devices.DCAM.DCAM), 613

[restart\\_lib\(\)](#) (in module `pylablib.devices.Mightex.MightexSSeries`), 708  
[restore\\_parameters\(\)](#) (pylablib.devices.Newport.picomotor.Picomotor8742 method), 736  
[retrieve\(\)](#) (pylablib.devices.Basler.pylon.BaslerPylonCameraRSInStgAF621000 method), 580  
[retry\\_clean\\_dir\(\)](#) (in module `pylablib.core.utils.files`), 418  
[retry\\_copy\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_copy\\_dir\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_ensure\\_dir\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_move\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_move\\_dir\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_remove\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_remove\\_dir\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_remove\\_dir\\_if\\_empty\(\)](#) (in module `pylablib.core.utils.files`), 417  
[retry\\_wait\(\)](#) (in module `pylablib.core.utils.general`), 428  
[RetryOnException](#) (class in `pylablib.core.utils.general`), 427  
[RetryOnException.ExceptionCatcher](#) (class in `pylablib.core.utils.general`), 428  
[revision\\_number](#) (pylablib.devices.HighFinesse.wlm.TDeviceInfo attribute), 626  
[right\\_enable](#) (pylablib.devices.Trinamic.base.TLimitSwitchParameters attribute), 971  
[RigoldG1000](#) (class in `pylablib.devices.AWG.specific`), 498  
[rise\\_speed](#) (pylablib.devices.Sirah.Matisse.TScanParameters attribute), 856  
[rng](#) (pylablib.devices.Keithley.mmultimeter.TConfigurationParameters attribute), 666  
[rng](#) (pylablib.devices.Keithley.mmultimeter.TFrequencyFunctionParameters attribute), 666  
[rng](#) (pylablib.devices.Keithley.mmultimeter.TGenericFunctionParameters attribute), 666  
[rng](#) (pylablib.devices.Ophir.base.TWavelengthInfo attribute), 751  
[ROI](#) (class in `pylablib.core.dataproc.image`), 148  
[roi](#) (pylablib.devices.interface.camera.TStatusLineDescription attribute), 1019  
[rom\\_version](#) (pylablib.devices.Ophir.base.TDeviceInfo attribute), 751  
[rotated2d\(\)](#) (pylablib.core.dataproc.transform.Indexed2DTransform method), 162  
[rotated2d\(\)](#) (pylablib.core.dataproc.transform.LinearTransform method), 162  
[round\\_significant\(\)](#) (in module `pylablib.core.utils.numerical`), 444  
[route](#) (pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParameters attribute), 942  
[RSInStgAF621000](#) (class in `pylablib.devices.AWG.specific`), 486  
[run\(\)](#) (pylablib.core.thread.controller.QTaskThread method), 353  
[run\(\)](#) (pylablib.core.thread.controller.QThreadController method), 344  
[run\(\)](#) (pylablib.core.thread.controller.QThreadControllerThread method), 341  
[run\\_as\\_batch\\_job\(\)](#) (pylablib.core.thread.controller.QTaskThread method), 353  
[run\\_device\\_service\(\)](#) (in module `pylablib.core.utils.rpyc_utils`), 447  
[running\(\)](#) (pylablib.core.thread.controller.QTaskThread method), 359  
[running\(\)](#) (pylablib.core.thread.controller.QThreadController method), 348  
[running\(\)](#) (pylablib.core.thread.controller.QThreadControllerThread method), 341  
[running\(\)](#) (pylablib.core.thread.controller.QTaskThread method), 353  
[running\(\)](#) (pylablib.core.thread.controller.QThreadController method), 348  
[running\(\)](#) (pylablib.core.thread.controller.QThreadControllerThread method), 341  
[RunningDebounceFilter](#) (class in `pylablib.core.dataproc.filters`), 140  
[RunningDecimationFilter](#) (class in `pylablib.core.dataproc.filters`), 140

## S

[same](#) (pylablib.core.utils.dictionary.DictionaryDiff attribute), 385  
[sample\\_per\\_chan](#) (pylablib.devices.NI.daq.TVoltageOutputClockParameters attribute), 718  
[save\(\)](#) (pylablib.devices.BitFlow.BitFlow.CameraFileEditor method), 596  
[save\\_bin\(\)](#) (in module `pylablib.core.fileio.savefile`), 229  
[save\\_bin\\_desc\(\)](#) (in module `pylablib.core.fileio.savefile`), 229  
[save\\_csv\(\)](#) (in module `pylablib.core.fileio.savefile`), 228  
[save\\_csv\\_desc\(\)](#) (in module `pylablib.core.fileio.savefile`), 228  
[save\\_dict\(\)](#) (in module `pylablib.core.fileio.savefile`), 229  
[save\\_file\(\)](#) (pylablib.core.fileio.dict\_entry.ExternalNumpyDictionaryEntry method), 209  
[save\\_file\(\)](#) (pylablib.core.fileio.dict\_entry.IExternalFileDictionaryEntry method), 209  
[save\\_generic\(\)](#) (in module `pylablib.core.fileio.savefile`), 230  
[save\\_parameters\(\)](#) (pylablib.devices.Newport.picomotor.Picomotor8742 method), 736

- `save_preset()` (*pylablib.devices.OZOptics.base.EPC04* *method*), 745
- `scale()` (*pylablib.core.dataproc.ctransform\_fallback.CLineSQUIDTransform* *method*), 134
- `scan_both_motors()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `scan_both_motors_quick()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 866
- `scan_centered()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `scan_coarse_gen()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 867
- `scan_devices()` (*pylablib.devices.Newport.picomotor.Picomotor674* *method*), 737
- `scan_quick()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `scan_quick_centered()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `scan_steps()` (*pylablib.devices.Sirah.tuner.MatisseTuner* *method*), 865
- `schedule()` (*pylablib.core.thread.callsync.QDirectCallScheduler* *method*), 334
- `schedule()` (*pylablib.core.thread.callsync.QMulticastThreadCallScheduler* *method*), 340
- `schedule()` (*pylablib.core.thread.callsync.QMultiQueueScheduler* *method*), 339
- `schedule()` (*pylablib.core.thread.callsync.QQueueLengthLimitScheduler* *method*), 337
- `schedule()` (*pylablib.core.thread.callsync.QQueueScheduler* *method*), 335
- `schedule()` (*pylablib.core.thread.callsync.QQueueSizeLimitScheduler* *method*), 339
- `schedule()` (*pylablib.core.thread.callsync.QScheduler* *method*), 333
- `schedule()` (*pylablib.core.thread.callsync.QThreadCallScheduler* *method*), 339
- `schedule()` (*pylablib.core.thread.controller.QTaskThread.Job* *method*), 351
- `schedule_multiple_queues()` (in module *pylablib.core.thread.callsync*), 339
- `scheduled` (*pylablib.devices.PCO.SC2.TInternalBufferStatus* *attribute*), 755
- `scheduled_max` (*pylablib.devices.PCO.SC2.TInternalBufferStatus* *attribute*), 755
- `scheduler` (*pylablib.core.thread.controller.QTaskThread.TController* *attribute*), 351
- `scmd` (*pylablib.devices.Standa.base.TFullState* *attribute*), 877
- `SCPIDevice` (class in *pylablib.core.devio.SCPI*), 165
- `SCPIDevice.NoParameterCaller` (class in *pylablib.core.devio.SCPI*), 168
- `search_frequency()` (*pylablib.devices.Thorlabs.elliptec.ElliptecMotor* *method*), 914
- `search_speed` (*pylablib.devices.Trinamic.base.THomeParams* *attribute*), 972
- `second` (*pylablib.devices.uc480.uc480.TTimestamp* *attribute*), 1024
- `section()` (*pylablib.core.devio.backend\_logger.BackendLogger* *method*), 169
- `section()` (*pylablib.core.devio.comm\_backend.RecordedDeviceBackend* *method*), 190
- `select_axis()` (*pylablib.devices.PhysikInstrumente.base.PIE515* *method*), 820
- `select_channel()` (*pylablib.devices.Cryomagnetics.base.LM500* *method*), 604
- `select_channel()` (*pylablib.devices.Cryomagnetics.base.LM510* *method*), 611
- `select_channel()` (*pylablib.devices.Lakeshore.base.Lakeshore370* *method*), 678
- `select_channel()` (*pylablib.devices.Tektronix.base.DPO2000* *method*), 899
- `select_channel()` (*pylablib.devices.Tektronix.base.ITektronixScope* *method*), 883
- `select_channel()` (*pylablib.devices.Tektronix.base.TDS2000* *method*), 892
- `select_current_channel()` (*pylablib.devices.AWG.generic.GenericAWG* *method*), 456
- `select_current_channel()` (*pylablib.devices.AWG.specific.Agilent33220A* *method*), 471
- `select_current_channel()` (*pylablib.devices.AWG.specific.Agilent33500* *method*), 465
- `select_current_channel()` (*pylablib.devices.AWG.specific.InstekAFG2000* *method*), 484
- `select_current_channel()` (*pylablib.devices.AWG.specific.InstekAFG2225* *method*), 478
- `select_current_channel()` (*pylablib.devices.AWG.specific.RigolDG1000* *method*), 502
- `select_current_channel()` (*pylablib.devices.AWG.specific.RSInstekAFG21000* *method*), 502



- method), 490
- select\_current\_channel() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 496
- senc (pylablib.devices.Standa.base.TFullState attribute), 877
- send() (pylablib.core.thread.multicast\_pool.MulticastPool method), 365
- send() (pylablib.core.utils.ipc.IIPCChannel method), 435
- send() (pylablib.core.utils.ipc.PipeIPCChannel method), 435
- send() (pylablib.core.utils.ipc.SharedMemIPCChannel method), 436
- send() (pylablib.core.utils.net.ClientSocket method), 443
- send\_ack() (pylablib.core.utils.net.ClientSocket method), 443
- send\_comm() (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913
- send\_comm() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 347
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 916
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 923
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 934
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 941
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 938
- send\_comm() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 945
- send\_comm() (pylablib.devices.Thorlabs.kinesis.MFF method), 927
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice method), 916
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.KinesisDevice method), 923
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 934
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoControl method), 941
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 938
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 945
- send\_comm\_data() (pylablib.devices.Thorlabs.kinesis.MFF method), 927
- send\_command() (pylablib.devices.Leybold.base.GenericITR method), 686
- send\_command() (pylablib.devices.Leybold.base.ITR90 method), 689
- send\_declen() (pylablib.core.utils.net.ClientSocket method), 443
- send\_delimiter() (pylablib.core.utils.net.ClientSocket method), 443
- send\_fixedlen() (pylablib.core.utils.net.ClientSocket method), 443
- send\_interrupt() (pylablib.core.thread.controller.QTaskThread method), 359
- send\_interrupt() (pylablib.core.thread.controller.QThreadController method), 347
- send\_message() (pylablib.core.thread.controller.QTaskThread method), 359
- send\_message() (pylablib.core.thread.controller.QThreadController method), 347
- send\_message() (pylablib.devices.Voltcraft.multimeter.VC880 method), 985
- send\_multicast() (pylablib.core.thread.controller.QTaskThread method), 359
- send\_multicast() (pylablib.core.thread.controller.QThreadController method), 346
- send\_multicast\_sync() (pylablib.core.thread.controller.QTaskThread method), 360
- send\_multicast\_sync() (pylablib.core.thread.controller.QThreadController method), 346
- send\_numpy() (pylablib.core.utils.ipc.IIPCChannel method), 435
- send\_numpy() (pylablib.core.utils.ipc.PipeIPCChannel method), 435
- send\_numpy() (pylablib.core.utils.ipc.SharedMemIPCChannel method), 436
- send\_software\_trigger() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519
- send\_software\_trigger() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 527
- send\_software\_trigger() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 616
- send\_software\_trigger() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 646
- send\_software\_trigger() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 646

`lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` attribute), 771  
`method`), 636  
`send_software_trigger()` (py-serial (pylablib.devices.SiliconSoftware.fgrab.TBoardInfo attribute), 838  
`lablib.devices.Mightex.MightexSSeries.MightexSSeries` (pylablib.devices.SmarAct.MCS2.TDeviceInfo attribute), 869  
`method`), 709  
`send_software_trigger()` (py-serial (pylablib.devices.Thorlabs.misc.TPMDeviceInfo attribute), 945  
`lablib.devices.PCO.SC2.PCOSC2Camera` serial (pylablib.devices.Thorlabs.misc.TPMSensorInfo attribute), 945  
`method`), 756  
`send_software_trigger()` (py-serial (pylablib.devices.Toptica.ibeam.TDeviceInfo attribute), 968  
`lablib.devices.Photometrics.pvcam.PvcamCamera` serial (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera attribute), 519  
`method`), 774  
`send_software_trigger()` (py-serial\_flush() (pylablib.devices.IMAQ.IMAQ.IMAQCamera attribute), 646  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera` serial\_flush() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber attribute), 637  
`method`), 794  
`send_software_trigger()` (py-serial\_flush() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera attribute), 794  
`method`), 905  
`send_sync()` (pylablib.core.thread.controller.QTaskThread serial\_flush() (pylablib.devices.ElektroAutomatik.base.TDeviceInfo attribute), 622  
`method`), 360  
`send_sync()` (pylablib.core.thread.controller.QThreadControl serial\_no (pylablib.devices.Thorlabs.elliptec.TDeviceInfo attribute), 911  
`method`), 347  
`sens_id` (pylablib.devices.uc480.uc480.TCameraInfo attribute), 1023  
`sensor` (pylablib.devices.Leybold.base.TDeviceInfo attribute), 685  
`sensor` (pylablib.devices.PCO.SC2.TDeviceInfo attribute), 754  
`sensor_type` (pylablib.devices.Thorlabs.TLCamera.TSensorInfo attribute), 903  
`serial` (pylablib.core.devio.hid.TDeviceDescription attribute), 194  
`serial` (pylablib.devices.Attocube.anc300.TDeviceInfo attribute), 566  
`serial` (pylablib.devices.Basler.pylon.TCameraInfo attribute), 575  
`serial` (pylablib.devices.Basler.pylon.TDeviceInfo attribute), 577  
`serial` (pylablib.devices.Hubner.Cobolt.TDeviceInfo attribute), 630  
`serial` (pylablib.devices.Lakeshore.base.TLakeshore218C serial\_number (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 648  
`attribute`), 672  
`serial` (pylablib.devices.LaserQuantum.base.TDeviceInfo serial\_number (pylablib.devices.IMAQdx.IMAQdx.TDeviceInfo attribute), 650  
`attribute`), 682  
`serial` (pylablib.devices.LighthousePhotonics.base.TDeviceInfo serial\_number (pylablib.devices.NI.daq.TDeviceInfo attribute), 718  
`attribute`), 690  
`serial` (pylablib.devices.Mightex.MightexSSeries.TCameraInfo serial\_number (pylablib.devices.PCO.SC2.TDeviceInfo attribute), 754  
`attribute`), 707  
`serial` (pylablib.devices.Mightex.MightexSSeries.TDeviceInfo serial\_number (pylablib.devices.PhotonFocus.PhotonFocus.TDeviceInfo attribute), 781  
`attribute`), 708  
`serial` (pylablib.devices.Ophir.base.TDeviceInfo attribute), 751  
`serial` (pylablib.devices.Ophir.base.THeadInfo attribute), 750  
`serial` (pylablib.devices.Photometrics.pvcam.TDeviceInfo serial\_number (pylablib.devices.Thorlabs.TLCamera.TDeviceInfo attribute), 905

attribute), 903  
 serial\_number (pylablib.devices.uc480.uc480.TCameraInfo attribute), 1023  
 serial\_number (pylablib.devices.uc480.uc480.TDeviceInfo attribute), 1023  
 serial\_query() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519  
 serial\_query() (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 508  
 serial\_read() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519  
 serial\_read() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 646  
 serial\_read() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 637  
 serial\_read() (pylablib.devices.PhotonFocus.PhotonFocusPhotonFocusIMAQCamera method), 794  
 serial\_readline() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519  
 serial\_readline() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 646  
 serial\_readline() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 637  
 serial\_readline() (pylablib.devices.PhotonFocus.PhotonFocusPhotonFocusIMAQCamera method), 794  
 serial\_write() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519  
 serial\_write() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 646  
 serial\_write() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 636  
 serial\_write() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 794  
 SerialDeviceBackend (class in pylablib.core.devio.comm\_backend), 175  
 Series1DWrapper (class in pylablib.core.dataproc.table\_wrap), 155  
 Series1DWrapper.Accessor (class in pylablib.core.dataproc.table\_wrap), 155  
 set() (pylablib.core.utils.functions.AttrObjectProperty method), 424  
 set() (pylablib.core.utils.functions.IObjectProperty method), 423  
 set() (pylablib.core.utils.functions.MethodObjectProperty method), 424  
 set\_accessory\_state() (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548  
 set\_acquisition\_mode() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 527  
 set\_active\_channel() (pylablib.devices.HighFinesse.wlm.WLM method), 628  
 set\_addr() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 737  
 set\_all\_attribute\_values() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 537  
 set\_all\_attribute\_values() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 578  
 set\_all\_attribute\_values() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 616  
 set\_all\_attribute\_values() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 661  
 set\_all\_attribute\_values() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 651  
 set\_all\_attribute\_values() (pylablib.devices.interface.camera.IAttributeCamera method), 996  
 set\_all\_attribute\_values() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 772  
 set\_all\_attribute\_values() (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 782  
 set\_all\_attribute\_values() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 810  
 set\_all\_attribute\_values() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 803  
 set\_all\_attribute\_values() (pylablib.devices.PrincetonInstruments.picam.PicamCamera method), 828  
 set\_all\_frequencies() (pylablib.devices.OZOptics.base.EPC04 method), 745  
 set\_all\_grabber\_attribute\_values() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1001  
 set\_all\_grabber\_attribute\_values() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 803  
 set\_all\_grabber\_attribute\_values() (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera method), 852

<code>set_all_grabber_attribute_values()</code> (py-lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber method), 842	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QContainer method), 240
<code>set_all_indicators()</code> (py-lablib.core.gui.value_handling.GUIValues method), 329	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QDialogContainer method), 258
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.IQContainer method), 238	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QFrameContainer method), 254
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 244	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 263
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QContainer method), 240	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QScrollAreaContainer method), 271
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QDialogContainer method), 258	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 268
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QFrameContainer method), 254	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QTabContainer method), 274
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 263	<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.QWidgetContainer method), 249
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QScrollAreaContainer method), 271	<code>set_all_values()</code> (py-lablib.core.gui.widgets.param_table.ParamTable method), 291
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 268	<code>set_all_values()</code> (py-lablib.core.gui.widgets.param_table.StatusTable method), 305
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QTabContainer method), 274	<code>set_all_voltages()</code> (py-lablib.devices.OZOptics.base.EPC04 method), 745
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.container.QWidgetContainer method), 249	<code>set_amp_mode()</code> (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 525
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.param_table.ParamTable method), 292	<code>set_amplitude()</code> (py-lablib.devices.AWG.generic.GenericAWG method), 456
<code>set_all_indicators()</code> (py-lablib.core.gui.widgets.param_table.StatusTable method), 305	<code>set_amplitude()</code> (py-lablib.devices.AWG.specific.Agilent33220A method), 471
<code>set_all_relays()</code> (py-lablib.devices.Conrad.base.RelayBoard method), 598	<code>set_amplitude()</code> (py-lablib.devices.AWG.specific.Agilent33500 method), 465
<code>set_all_values()</code> (py-lablib.core.gui.value_handling.GUIValues method), 329	<code>set_amplitude()</code> (py-lablib.devices.AWG.specific.InstekAFG2000 method), 484
<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.IQContainer method), 238	<code>set_amplitude()</code> (py-lablib.devices.AWG.specific.InstekAFG2225 method), 474
<code>set_all_values()</code> (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 244	<code>set_amplitude()</code> (py-lablib.devices.AWG.specific.RigolDG1000 method), 502
	<code>set_amplitude()</code> (py- method), 502



- lablib.devices.AWG.specific.RSInstekAFG21000* method), 490
- set\_amplitude()* (py-  
*lablib.devices.AWG.specific.TektronixAFG1000* method), 496
- set\_analog\_modulation\_impedance()* (py-  
*lablib.devices.Hubner.Cobolt.Cobolt* method), 632
- set\_analog\_output\_value()* (py-  
*lablib.devices.Lakeshore.base.Lakeshore218* method), 674
- set\_analog\_output\_value()* (py-  
*lablib.devices.Lakeshore.base.Lakeshore370* method), 678
- set\_attenuation()* (py-  
*lablib.devices.OZOptics.base.DD100* method), 743
- set\_attribute\_value()* (py-  
*lablib.devices.Andor.AndorSDK3.AndorSDK3Camera* method), 537
- set\_attribute\_value()* (py-  
*lablib.devices.Basler.pylon.BaslerPylonCamera* method), 578
- set\_attribute\_value()* (py-  
*lablib.devices.DCAM.DCAM.DCAMCamera* method), 616
- set\_attribute\_value()* (py-  
*lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera* method), 661
- set\_attribute\_value()* (py-  
*lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera* method), 651
- set\_attribute\_value()* (py-  
*lablib.devices.interface.camera.IAttributeCamera* method), 996
- set\_attribute\_value()* (py-  
*lablib.devices.Photometrics.pvcam.PvcamCamera* method), 772
- set\_attribute\_value()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera* method), 782
- set\_attribute\_value()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera* method), 810
- set\_attribute\_value()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera* method), 795
- set\_attribute\_value()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera* method), 803
- set\_attribute\_value()* (py-  
*lablib.devices.PrincetonInstruments.picam.PicamCamera* method), 828
- set\_axis()* (pylablib.devices.PhytikInstrumente.base.PIE516 method), 814
- set\_axis()* (pylablib.devices.PhytikInstrumente.base.PIE516 method), 819
- set\_axis\_correction()* (py-  
*lablib.devices.Attocube.anc300.ANC300* method), 568
- set\_axis\_dir()* (pylablib.devices.SmarAct.scu3d.SCUD method), 874
- set\_axis\_parameter()* (py-  
*lablib.devices.PhytikInstrumente.base.GenericPIController* method), 815
- set\_axis\_parameter()* (py-  
*lablib.devices.PhytikInstrumente.base.PIE516* method), 819
- set\_axis\_parameter()* (py-  
*lablib.devices.Trinamic.base.TMCM1110* method), 972
- set\_axis\_parameter()* (py-  
*lablib.devices.Trinamic.base.TMCMx110* method), 979
- set\_axis\_speed()* (py-  
*lablib.devices.Arcus.performax.Performax2EXStage* method), 559
- set\_axis\_speed()* (py-  
*lablib.devices.Arcus.performax.Performax4EXStage* method), 554
- set\_axis\_speed()* (py-  
*lablib.devices.Arcus.performax.PerformaxDMXJSASStage* method), 561
- set\_baudrate()* (pylablib.devices.Arcus.performax.Performax2EXStage method), 559
- set\_baudrate()* (pylablib.devices.Arcus.performax.Performax4EXStage method), 553
- set\_baudrate()* (pylablib.devices.Ophir.base.VegaPowerMeter method), 753
- set\_binning()* (pylablib.devices.uc480.uc480.UC480Camera method), 1027
- set\_bit\_alignment()* (py-  
*lablib.devices.PCO.SC2.PCOS2Camera* method), 759
- set\_black\_level()* (py-  
*lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera* method), 806
- set\_black\_level\_offset()* (py-  
*lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera* method), 519
- set\_black\_level\_offset()* (py-  
*lablib.devices.AlliedVision.Bonito.IBonitoCamera* method), 509
- set\_black\_level\_offset()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera* method), 784
- set\_black\_level\_offset()* (py-  
*lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera* method), 810

- method*), 811
- `set_black_level_offset()` (`py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCUI`), 795
- `set_black_level_offset()` (`py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCUI`), 803
- `set_burst_mode()` (`py-lablib.devices.AWG.generic.GenericAWG`), 458
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.Agilent33220A`), 471
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.Agilent33500`), 465
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.InstekAFG2000`), 484
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.InstekAFG2225`), 478
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.RigolDG1000`), 502
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.RSInstekAFG21000`), 490
- `set_burst_mode()` (`py-lablib.devices.AWG.specific.TektronixAFG1000`), 496
- `set_burst_ncycles()` (`py-lablib.devices.AWG.generic.GenericAWG`), 458
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.Agilent33220A`), 472
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.Agilent33500`), 465
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.InstekAFG2000`), 484
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.InstekAFG2225`), 478
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.RigolDG1000`), 502
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.RSInstekAFG21000`), 490
- `set_burst_ncycles()` (`py-lablib.devices.AWG.specific.TektronixAFG1000`), 496
- method*), 496
- `set_buttons_width()` (`py-lablib.core.gui.widgets.button_selector.ButtonSelector`), 233
- `set_by_name()` (`pylablib.core.gui.widgets.container.QTabContainer`), 272
- `set_calibration_factor()` (`py-lablib.devices.Pfeiffer.base.TPG260`), 765
- `set_camera_id()` (`py-lablib.devices.uc480.uc480.UC480Camera`), 1025
- `set_cap_function_parameters()` (`py-lablib.devices.Keithley.multimeter.Keithley2110`), 667
- `set_channel_power()` (`py-lablib.devices.Toptica.ibeam.TopticaIBeam`), 969
- `set_clear_cycles()` (`py-lablib.devices.Photometrics.pvcam.PvcamCamera`), 774
- `set_clear_mode()` (`py-lablib.devices.Photometrics.pvcam.PvcamCamera`), 774
- `set_color_format()` (`py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera`), 904
- `set_color_mode()` (`py-lablib.devices.uc480.uc480.UC480Camera`), 1026
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.IQWidgetContainer`), 244
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.QDialogContainer`), 258
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.QFrameContainer`), 254
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.QGroupBoxContainer`), 263
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer`), 268
- `set_column_stretch()` (`py-lablib.core.gui.widgets.container.QWidgetContainer`), 249
- `set_column_stretch()` (`py-lablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget`), 281
- `set_column_stretch()` (`py-lablib.core.gui.widgets.layout_manager.QLayoutManagedWidget`), 283

<code>set_column_stretch()</code>	(py-lablib.core.gui.widgets.param_table.ParamTable method), 294	<code>set_data_pts_range()</code>	(py-lablib.devices.Tektronix.base.TDS2000 method), 884
<code>set_column_stretch()</code>	(py-lablib.core.gui.widgets.param_table.StatusTable method), 305	<code>set_default_addr()</code>	(py-lablib.devices.Thorlabs.elliptec.ElliptecMotor method), 893
<code>set_configuration()</code>	(py-lablib.devices.Keithley.multimeter.Keithley2110 method), 667	<code>set_default_axis()</code>	(py-lablib.devices.SmarAct.MCS2.MCS2 method), 912
<code>set_container()</code>	(py-lablib.core.dataproc.table_wrap.Array2DWrappers method), 157	<code>set_default_channel()</code>	(py-lablib.devices.HighFinesse.wlm.WLM method), 870
<code>set_control_mode()</code>	(py-lablib.devices.Cryomagnetics.base.LM510 method), 608	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisDevice method), 627
<code>set_cooler()</code>	(pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 524	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 921
<code>set_cooler()</code>	(pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 538	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 934
<code>set_coupling()</code>	(pylablib.devices.Tektronix.base.DPO2000 method), 899	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 941
<code>set_coupling()</code>	(pylablib.devices.Tektronix.base.ITektronixScope method), 883	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 938
<code>set_coupling()</code>	(pylablib.devices.Tektronix.base.TDS2000 method), 893	<code>set_default_channel()</code>	(py-lablib.devices.Thorlabs.kinesis.MFF method), 927
<code>set_current()</code>	(pylablib.devices.ElektroAutomatik.base.PS2000 method), 624	<code>set_defect_correct_mode()</code>	(py-lablib.devices.DCAM.DCAM.DCAMCamera method), 617
<code>set_current()</code>	(pylablib.devices.Rigol.power_supply.DP1116A method), 835	<code>set_detector_offset()</code>	(py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546
<code>set_cursor_order()</code>	(py-lablib.core.gui.widgets.edit.NumEdit method), 276	<code>set_device_number()</code>	(py-lablib.devices.Arcus.performax.GenericPerformaxStage method), 551
<code>set_curve()</code>	(pylablib.devices.Lakeshore.base.Lakeshore218 method), 673	<code>set_device_number()</code>	(py-lablib.devices.Arcus.performax.Performax2EXStage method), 559
<code>set_curve_header()</code>	(py-lablib.devices.Lakeshore.base.Lakeshore218 method), 673	<code>set_device_number()</code>	(py-lablib.devices.Arcus.performax.Performax4EXStage method), 556
<code>set_custom_steps()</code>	(py-lablib.core.gui.widgets.edit.NumEdit method), 276	<code>set_device_number()</code>	(py-lablib.devices.Arcus.performax.PerformaxDMXJSAStage method), 563
<code>set_data_format()</code>	(py-lablib.devices.Tektronix.base.DPO2000 method), 899	<code>set_device_variable()</code>	(py-lablib.core.devio.comm_backend.ICommBackendWrapper method), 192
<code>set_data_format()</code>	(py-lablib.devices.Tektronix.base.ITektronixScope method), 884	<code>set_device_variable()</code>	(py-lablib.core.devio.interface.IDevice method), 197
<code>set_data_format()</code>	(py-lablib.devices.Tektronix.base.TDS2000 method), 893	<code>set_device_variable()</code>	(py-lablib.core.devio.SCP1.SCPIDevice method), 197
<code>set_data_pts_range()</code>	(py-lablib.devices.Tektronix.base.DPO2000 method), 900		
<code>set_data_pts_range()</code>	(py-lablib.devices.Tektronix.base.ITektronixScope method), 900		

168		method), 478
set_device_variable()	(py- lablib.devices.Agilent.pressure.XGS600 method), 507	set_device_variable() (py- lablib.devices.AWG.specific.RigolDG1000 method), 502
set_device_variable()	(py- lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 519	set_device_variable() (py- lablib.devices.AWG.specific.RSInstekAFG21000 method), 490
set_device_variable()	(py- lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 512	set_device_variable() (py- lablib.devices.AWG.specific.TektronixAFG1000 method), 496
set_device_variable()	(py- lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 533	set_device_variable() (py- lablib.devices.Basler.pylon.BaslerPylonCamera method), 583
set_device_variable()	(py- lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 542	set_device_variable() (py- lablib.devices.BitFlow.BitFlow.BitFlowCamera method), 595
set_device_variable()	(py- lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 549	set_device_variable() (py- lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 590
set_device_variable()	(py- lablib.devices.Arcus.performax.GenericPerformaxStage method), 552	set_device_variable() (py- lablib.devices.Conrad.base.RelayBoard method), 599
set_device_variable()	(py- lablib.devices.Arcus.performax.Performax2EXStage method), 559	set_device_variable() (py- lablib.devices.Cryocon.base.Cryocon1x method), 602
set_device_variable()	(py- lablib.devices.Arcus.performax.Performax4EXStage method), 556	set_device_variable() (py- lablib.devices.Cryomagnetics.base.LM500 method), 607
set_device_variable()	(py- lablib.devices.Arcus.performax.PerformaxDMXJSASStage method), 563	set_device_variable() (py- lablib.devices.Cryomagnetics.base.LM510 method), 611
set_device_variable()	(py- lablib.devices.Arduino.base.IArduinoDevice method), 565	set_device_variable() (py- lablib.devices.DCAM.DCAM.DCAMCamera method), 620
set_device_variable()	(py- lablib.devices.Attocube.anc300.ANC300 method), 569	set_device_variable() (py- lablib.devices.ElektroAutomatik.base.PS2000B method), 625
set_device_variable()	(py- lablib.devices.Attocube.anc350.ANC350 method), 573	set_device_variable() (py- lablib.devices.HighFinesse.wlm.WLM method), 629
set_device_variable()	(py- lablib.devices.AWG.generic.GenericAWG method), 460	set_device_variable() (py- lablib.devices.Hubner.Cobolt.Cobolt method), 632
set_device_variable()	(py- lablib.devices.AWG.specific.Agilent33220A method), 472	set_device_variable() (py- lablib.devices.IMAQ.IMAQ.IMAQCamera method), 646
set_device_variable()	(py- lablib.devices.AWG.specific.Agilent33500 method), 466	set_device_variable() (py- lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 640
set_device_variable()	(py- lablib.devices.AWG.specific.InstekAFG2000 method), 484	set_device_variable() (py- lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 661
set_device_variable()	(py- lablib.devices.AWG.specific.InstekAFG2225 method), 484	set_device_variable() (py- lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 661

- method*), 655
- `set_device_variable()` (py-lablib.devices.interface.camera.IAttributeCamera *method*), 999
- `set_device_variable()` (py-lablib.devices.interface.camera.IBinROICamera *method*), 1018
- `set_device_variable()` (py-lablib.devices.interface.camera.ICamera *method*), 994
- `set_device_variable()` (py-lablib.devices.interface.camera.IExposureCamera *method*), 1009
- `set_device_variable()` (py-lablib.devices.interface.camera.IGrabberAttributeCamera *method*), 1004
- `set_device_variable()` (py-lablib.devices.interface.camera.IROICamera *method*), 1013
- `set_device_variable()` (py-lablib.devices.interface.stage.IMultiaxisStage *method*), 1022
- `set_device_variable()` (py-lablib.devices.interface.stage.IStage *method*), 1021
- `set_device_variable()` (py-lablib.devices.Keithley.multimeter.Keithley2110 *method*), 670
- `set_device_variable()` (py-lablib.devices.KJL.base.KJL300 *method*), 665
- `set_device_variable()` (py-lablib.devices.Lakeshore.base.Lakeshore218 *method*), 676
- `set_device_variable()` (py-lablib.devices.Lakeshore.base.Lakeshore370 *method*), 680
- `set_device_variable()` (py-lablib.devices.LaserQuantum.base.Finesse *method*), 684
- `set_device_variable()` (py-lablib.devices.Leybold.base.GenericITR *method*), 687
- `set_device_variable()` (py-lablib.devices.Leybold.base.ITR90 *method*), 689
- `set_device_variable()` (py-lablib.devices.LighthousePhotonics.base.SproutG *method*), 691
- `set_device_variable()` (py-lablib.devices.Lumel.base.LumelRE72Controller *method*), 694
- `set_device_variable()` (py-lablib.devices.M2.base.ICEBlocDevice *method*), 697
- `set_device_variable()` (py-lablib.devices.M2.emm.EMM *method*), 700
- `set_device_variable()` (py-lablib.devices.M2.solstis.Solstis *method*), 707
- `set_device_variable()` (py-lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera *method*), 713
- `set_device_variable()` (py-lablib.devices.Modbus.modbus.GenericModbusRTUDevice *method*), 717
- `set_device_variable()` (py-lablib.devices.Newport.picomotor.Picomotor8742 *method*), 739
- `set_device_variable()` (py-lablib.devices.NI.daq.NIDAQ *method*), 725
- `set_device_variable()` (py-lablib.devices.NKT.interbus.GenericInterbusDevice *method*), 727
- `set_device_variable()` (py-lablib.devices.NKT.interbus.GenericInterbusModule *method*), 729
- `set_device_variable()` (py-lablib.devices.NKT.interbus.IInterbusModule *method*), 728
- `set_device_variable()` (py-lablib.devices.NKT.interbus.InterbusSystem *method*), 735
- `set_device_variable()` (py-lablib.devices.NKT.interbus.SuperKExtremeInterbusModule *method*), 730
- `set_device_variable()` (py-lablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule *method*), 731
- `set_device_variable()` (py-lablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule *method*), 732
- `set_device_variable()` (py-lablib.devices.NKT.interbus.SuperKSelectInterbusModule *method*), 733
- `set_device_variable()` (py-lablib.devices.Omron.base.OmronE5xCController *method*), 748
- `set_device_variable()` (py-lablib.devices.Ophir.base.OphirDevice *method*), 750
- `set_device_variable()` (py-lablib.devices.Ophir.base.VegaPowerMeter *method*), 754
- `set_device_variable()` (py-lablib.devices.OZOptics.base.DD100 *method*), 744
- `set_device_variable()` (py-



<code>lablib.devices.OZOptics.base.EPC04</code> method), 746	<code>lablib.devices.Sirah.Matisse.SirahMatisse</code> method), 862
<code>set_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.OZOpticsDevice</code> method), 741	<code>set_device_variable()</code> (py- <code>lablib.devices.SmarAct.MCS2.MCS2</code> method), 873
<code>set_device_variable()</code> (py- <code>lablib.devices.OZOptics.base.TF100</code> method), 743	<code>set_device_variable()</code> (py- <code>lablib.devices.SmarAct.scu3d.SC3D</code> method), 876
<code>set_device_variable()</code> (py- <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> method), 762	<code>set_device_variable()</code> (py- <code>lablib.devices.Standa.base.Standa8SMC</code> method), 880
<code>set_device_variable()</code> (py- <code>lablib.devices.Pfeiffer.base.DPG202</code> method), 769	<code>set_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.DPO2000</code> method), 900
<code>set_device_variable()</code> (py- <code>lablib.devices.Pfeiffer.base.TPG260</code> method), 767	<code>set_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.ITektronixScope</code> method), 887
<code>set_device_variable()</code> (py- <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> method), 778	<code>set_device_variable()</code> (py- <code>lablib.devices.Tektronix.base.TDS2000</code> method), 893
<code>set_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> method), 787	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.elliptec.ElliptecMotor</code> method), 915
<code>set_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlipper</code> method), 811	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.BasicKinesisDevice</code> method), 918
<code>set_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</code> method), 795	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisDevice</code> method), 923
<code>set_device_variable()</code> (py- <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> method), 803	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisMotor</code> method), 934
<code>set_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.GenericPIController</code> method), 816	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisPiezoController</code> method), 941
<code>set_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.PIE515</code> method), 822	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</code> method), 938
<code>set_device_variable()</code> (py- <code>lablib.devices.PhysikInstrumente.base.PIE516</code> method), 819	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.KinesisQuadDetector</code> method), 945
<code>set_device_variable()</code> (py- <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> method), 832	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.kinesis.MFF</code> method), 927
<code>set_device_variable()</code> (py- <code>lablib.devices.Rigol.power_supply.DP1116A</code> method), 837	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.misc.GenericPM</code> method), 949
<code>set_device_variable()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> method), 852	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.misc.PM160</code> method), 953
<code>set_device_variable()</code> (py- <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 847	<code>set_device_variable()</code> (py- <code>lablib.devices.Thorlabs.serial.FW</code> method), 960
<code>set_device_variable()</code> (py-	<code>set_device_variable()</code> (py-

`lablib.devices.Thorlabs.serial.FWv1` method), 963  
`set_device_variable()` (py-  
`lablib.devices.Thorlabs.serial.MDT69xA`  
method), 966  
`set_device_variable()` (py-  
`lablib.devices.Thorlabs.serial.ThorlabsSerialInterf`  
method), 956  
`set_device_variable()` (py-  
`lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera`  
method), 910  
`set_device_variable()` (py-  
`lablib.devices.Toptica.ibeam.TopicalIBeam`  
method), 970  
`set_device_variable()` (py-  
`lablib.devices.Trinamic.base.TMCM1110`  
method), 976  
`set_device_variable()` (py-  
`lablib.devices.Trinamic.base.TMCMx110`  
method), 979  
`set_device_variable()` (py-  
`lablib.devices.uc480.uc480.UC480Camera`  
method), 1030  
`set_device_variable()` (py-  
`lablib.devices.Voltcraft.multimeter.VC7055`  
method), 983  
`set_device_variable()` (py-  
`lablib.devices.Voltcraft.multimeter.VC880`  
method), 986  
`set_device_variable()` (py-  
`lablib.devices.Windows.joystick.Joystick`  
method), 989  
`set_diffuser()` (pylablib.devices.Ophir.base.VegaPowerMeter  
method), 753  
`set_digital_gain()` (py-  
`lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera`  
method), 519  
`set_digital_gain()` (py-  
`lablib.devices.AlliedVision.Bonito.IBonitoCamera`  
method), 509  
`set_digital_output()` (py-  
`lablib.devices.Arcus.performax.Performax2EXStage`  
method), 560  
`set_digital_output()` (py-  
`lablib.devices.Arcus.performax.Performax4EXStage`  
method), 555  
`set_digital_output()` (py-  
`lablib.devices.Arcus.performax.PerformaxDMXJSAStage`  
method), 563  
`set_digital_output_register()` (py-  
`lablib.devices.Arcus.performax.Performax2EXStage`  
method), 560  
`set_digital_output_register()` (py-  
`lablib.devices.Arcus.performax.Performax4EXStage`  
method), 555  
`set_digital_output_register()` (py-  
`lablib.devices.Arcus.performax.PerformaxDMXJSAStage`  
method), 563  
`set_digital_outputs()` (py-  
`lablib.devices.NI.daq.NIDAQ` method), 721  
`set_diode_power_lowlevel()` (py-  
`lablib.devices.Sirah.Matisse.SirahMatisse`  
method), 857  
`set_direct_index_action()` (py-  
`lablib.core.gui.widgets.button_selector.ButtonSelector`  
method), 232  
`set_direct_index_action()` (py-  
`lablib.core.gui.widgets.combo_box.ComboBox`  
method), 234  
`set_display_channel()` (py-  
`lablib.devices.Pfeiffer.base.TPG260` method), 765  
`set_display_resolution()` (py-  
`lablib.devices.Pfeiffer.base.TPG260` method), 765  
`set_display_units()` (py-  
`lablib.devices.Cryocon.base.Cryocon1x`  
method), 600  
`set_double_image_mode()` (py-  
`lablib.devices.PCO.SC2.PCOS2Camera`  
method), 759  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.generic.GenericAWG`  
method), 457  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.Agilent33220A`  
method), 472  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.Agilent33500`  
method), 466  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.InstekAFG2000`  
method), 484  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.InstekAFG2225`  
method), 478  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.RigolDG1000`  
method), 502  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.RSInstekAFG21000`  
method), 490  
`set_duty_cycle()` (py-  
`lablib.devices.AWG.specific.TektronixAFG1000`  
method), 496  
`set_edge_trigger_coupling()` (py-  
`lablib.devices.Tektronix.base.DPO2000`  
method), 900

`set_edge_trigger_coupling()` (py-lablib.devices.Tektronix.base.ITektronixScope method), 882  
`set_edge_trigger_coupling()` (py-lablib.devices.Tektronix.base.TDS2000 method), 893  
`set_edge_trigger_slope()` (py-lablib.devices.Tektronix.base.DPO2000 method), 900  
`set_edge_trigger_slope()` (py-lablib.devices.Tektronix.base.ITektronixScope method), 882  
`set_edge_trigger_slope()` (py-lablib.devices.Tektronix.base.TDS2000 method), 893  
`set_edge_trigger_source()` (py-lablib.devices.Tektronix.base.DPO2000 method), 900  
`set_edge_trigger_source()` (py-lablib.devices.Tektronix.base.ITektronixScope method), 882  
`set_edge_trigger_source()` (py-lablib.devices.Tektronix.base.TDS2000 method), 893  
`set_EMCCD_gain()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526  
`set_enabled()` (pylablib.core.gui.widgets.param\_table.ParameterTable method), 291  
`set_enabled()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 305  
`set_enabled()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 672  
`set_encoder_reference()` (py-lablib.devices.Arcus.performax.Performax2EXStage method), 560  
`set_encoder_reference()` (py-lablib.devices.Arcus.performax.Performax4EXStage method), 553  
`set_encoder_reference()` (py-lablib.devices.Standa.base.Standa8SMC method), 878  
`set_expandable()` (py-lablib.core.gui.widgets.edit.TextEdit method), 274  
`set_exposure()` (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCCamera method), 519  
`set_exposure()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 509  
`set_exposure()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 528  
`set_exposure()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 538  
`set_exposure()` (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 547  
`set_exposure()` (pylablib.devices.DCAM.DCAM.DCAMCamera method), 616  
`set_exposure()` (pylablib.devices.HighFinesse.wlm.WLM method), 627  
`set_exposure()` (pylablib.devices.interface.camera.IExposureCamera method), 1005  
`set_exposure()` (pylablib.devices.Mightex.MightexSSeries.MightexSSeries method), 709  
`set_exposure()` (pylablib.devices.PCO.SC2.PCOSC2Camera method), 757  
`set_exposure()` (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 773  
`set_exposure()` (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus method), 783  
`set_exposure()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 811  
`set_exposure()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 795  
`set_exposure()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 803  
`set_exposure()` (pylablib.devices.PrincetonInstruments.picam.PicamCamera method), 829  
`set_exposure()` (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 905  
`set_exposure()` (pylablib.devices.uc480.uc480.UC480Camera method), 1025  
`set_exposure_control_mode()` (py-lablib.devices.AlliedVision.Bonito.BonitoIMAQCCamera method), 520  
`set_exposure_control_mode()` (py-lablib.devices.AlliedVision.Bonito.IBonitoCamera method), 508  
`set_exposure_mode()` (py-lablib.devices.HighFinesse.wlm.WLM method), 627  
`set_external_input_modes()` (py-lablib.devices.Attocube.anc300.ANC300 method), 568  
`set_fan_mode()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526  
`set_fan_mode()` (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 773  
`set_fastpiezo_ctl_params()` (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_fastpiezo_ctl_status()` (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_fastpiezo_position()` (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_filter()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547



<code>set_filter()</code> ( <i>pylablib.devices.Ophir.base.VegaPowerMeter</i> method), 753	<code>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</code> method), 590
<code>set_fine_lock()</code> ( <i>pylablib.devices.Sirah.tuner.MatisseTuner</i> method), 866	<code>set_frame_format()</code> ( <i>pylablib.devices.DCAM.DCAM.DCAMCamera</i> method), 620
<code>set_first_valid_frame()</code> ( <i>pylablib.devices.interface.camera.FrameCounter</i> method), 995	<code>set_frame_format()</code> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 646
<code>set_fit_parameters()</code> ( <i>pylablib.core.dataproc.fitting.Fitter</i> method), 142	<code>set_frame_format()</code> ( <i>pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 640
<code>set_fixed_parameters()</code> ( <i>pylablib.core.dataproc.fitting.Fitter</i> method), 142	<code>set_frame_format()</code> ( <i>pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> method), 661
<code>set_flipper_port()</code> ( <i>pylablib.devices.Andor.Shamrock.ShamrockSpectrograph</i> method), 547	<code>set_frame_format()</code> ( <i>pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> method), 656
<code>set_float_formatter()</code> ( <i>pylablib.core.gui.widgets.edit.NumEdit</i> method), 276	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.IAttributeCamera</i> method), 999
<code>set_float_formatter()</code> ( <i>pylablib.core.gui.widgets.label.NumLabel</i> method), 279	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.IBinROICamera</i> method), 1018
<code>set_focus_mirror_position()</code> ( <i>pylablib.devices.Andor.Shamrock.ShamrockSpectrograph</i> method), 548	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.ICamera</i> method), 991
<code>set_formatter()</code> ( <i>pylablib.core.gui.widgets.edit.NumEdit</i> method), 276	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.IExposureCamera</i> method), 1009
<code>set_formatter()</code> ( <i>pylablib.core.gui.widgets.label.NumLabel</i> method), 279	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.IGrabberAttributeCamera</i> method), 1004
<code>set_frame_delay()</code> ( <i>pylablib.devices.PCO.SC2.PCOSC2Camera</i> method), 757	<code>set_frame_format()</code> ( <i>pylablib.devices.interface.camera.IROICamera</i> method), 1013
<code>set_frame_format()</code> ( <i>pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 520	<code>set_frame_format()</code> ( <i>pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> method), 713
<code>set_frame_format()</code> ( <i>pylablib.devices.AlliedVision.Bonito.IBonitoCamera</i> method), 512	<code>set_frame_format()</code> ( <i>pylablib.devices.PCO.SC2.PCOSC2Camera</i> method), 762
<code>set_frame_format()</code> ( <i>pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> method), 533	<code>set_frame_format()</code> ( <i>pylablib.devices.Photometrics.pvcam.PvcamCamera</i> method), 778
<code>set_frame_format()</code> ( <i>pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> method), 543	<code>set_frame_format()</code> ( <i>pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> method), 787
<code>set_frame_format()</code> ( <i>pylablib.devices.Basler.pylon.BaslerPylonCamera</i> method), 583	<code>set_frame_format()</code> ( <i>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa</i> method), 811
<code>set_frame_format()</code> ( <i>pylablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 595	<code>set_frame_format()</code> ( <i>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam</i> method), 795
<code>set_frame_format()</code> ( <i>pylablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 595	<code>set_frame_format()</code> ( <i>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam</i> method), 795

<code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> (method), 803	<code>lablib.devices.interface.camera.IAttributeCamera</code> (method), 999
<code>set_frame_format()</code> <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> (method), 832	<code>set_frame_info_format()</code> <code>lablib.devices.interface.camera.IBinROICamera</code> (method), 1018
<code>set_frame_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> (method), 853	<code>set_frame_info_format()</code> <code>lablib.devices.interface.camera.ICamera</code> (method), 992
<code>set_frame_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> (method), 847	<code>set_frame_info_format()</code> <code>lablib.devices.interface.camera.IExposureCamera</code> (method), 1009
<code>set_frame_format()</code> <code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> (method), 910	<code>set_frame_info_format()</code> <code>lablib.devices.interface.camera.IGrabberAttributeCamera</code> (method), 1004
<code>set_frame_format()</code> <code>lablib.devices.uc480.uc480.UC480Camera</code> (method), 1030	<code>set_frame_info_format()</code> <code>lablib.devices.interface.camera.IROICamera</code> (method), 1014
<code>set_frame_info_format()</code> <code>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</code> (method), 520	<code>set_frame_info_format()</code> <code>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</code> (method), 713
<code>set_frame_info_format()</code> <code>lablib.devices.AlliedVision.Bonito.IBonitoCamera</code> (method), 512	<code>set_frame_info_format()</code> <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> (method), 762
<code>set_frame_info_format()</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> (method), 533	<code>set_frame_info_format()</code> <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> (method), 778
<code>set_frame_info_format()</code> <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> (method), 543	<code>set_frame_info_format()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> (method), 787
<code>set_frame_info_format()</code> <code>lablib.devices.Basler.pylon.BaslerPylonCamera</code> (method), 583	<code>set_frame_info_format()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> (method), 811
<code>set_frame_info_format()</code> <code>lablib.devices.BitFlow.BitFlow.BitFlowCamera</code> (method), 595	<code>set_frame_info_format()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</code> (method), 795
<code>set_frame_info_format()</code> <code>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</code> (method), 590	<code>set_frame_info_format()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> (method), 803
<code>set_frame_info_format()</code> <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> (method), 620	<code>set_frame_info_format()</code> <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> (method), 832
<code>set_frame_info_format()</code> <code>lablib.devices.IMAQ.IMAQ.IMAQCamera</code> (method), 647	<code>set_frame_info_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> (method), 853
<code>set_frame_info_format()</code> <code>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</code> (method), 640	<code>set_frame_info_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> (method), 847
<code>set_frame_info_format()</code> <code>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</code> (method), 661	<code>set_frame_info_format()</code> <code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> (method), 910
<code>set_frame_info_format()</code> <code>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</code> (method), 656	<code>set_frame_info_format()</code> <code>lablib.devices.uc480.uc480.UC480Camera</code> (method), 1030
<code>set_frame_info_format()</code>	<code>set_frame_info_period()</code>

<i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 520	(py-	<i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> method), 713	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> method), 512	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> method), 762	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> method), 533	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.Photometrics.pvcam.PvcamCamera</i> method), 778	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> method), 543	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> method), 787	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> method), 584	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa</i> method), 811	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 595	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam</i> method), 795	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 590	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame</i> method), 804	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.DCAM.DCAM.DCAMCamera</i> method), 621	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.PrincetonInstruments.picam.PicamCamera</i> method), 832	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 647	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 853	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 640	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb</i> method), 847	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</i> method), 661	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> method), 910	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</i> method), 656	(py-	<i>set_frame_info_period()</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> method), 1030	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.IAttributeCamera</i> method), 1000	(py-	<i>set_frame_merge()</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame</i> method), 804	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.IBinROICamera</i> method), 1018	(py-	<i>set_frame_merge()</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 853	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.ICamera</i> method), 992	(py-	<i>set_frame_merge()</i> <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb</i> method), 842	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.IExposureCamera</i> method), 1009	(py-	<i>set_frame_period()</i> <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 520	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> method), 1004	(py-	<i>set_frame_period()</i> <i>lablib.devices.AlliedVision.Bonito.IBonitoCamera</i> method), 509	(py-
<i>set_frame_info_period()</i> <i>lablib.devices.interface.camera.IROICamera</i> method), 1014	(py-	<i>set_frame_period()</i> <i>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</i> method), 528	(py-
<i>set_frame_info_period()</i>	(py-	<i>set_frame_period()</i>	(py-

<i>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</i> <i>method</i> ), 538	<i>lablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 503
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.Basler.pylon.BaslerPylonCamera</i> <i>method</i> ), 579	<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 490
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.PCO.SC2.PCOSC2Camera</i> <i>method</i> ), 757	<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 496
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</i> <i>method</i> ), 783	<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.OZOptics.base.EPC04</i> <i>method</i> ), 745
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlareCamera</i> <i>method</i> ), 811	<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.Thorlabs.elliptec.ElliptecMotor</i> <i>method</i> ), 914
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</i> <i>method</i> ), 795	<i>set_frequency_average_time()</i> ( <i>py-</i> <i>lablib.devices.Sirah.tuner.MatisseTuner</i> <i>method</i> ), 865
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> <i>method</i> ), 804	<i>set_func_variable()</i> ( <i>py-</i> <i>lablib.core.thread.controller.QTaskThread</i> <i>method</i> ), 360
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 905	<i>set_func_variable()</i> ( <i>py-</i> <i>lablib.core.thread.controller.QThreadController</i> <i>method</i> ), 347
<i>set_frame_period()</i> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1025	<i>set_function()</i> ( <i>pylablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 456
<i>set_frameskip_behavior()</i> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1027	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 472
<i>set_freq_function_parameters()</i> ( <i>py-</i> <i>lablib.devices.Keithley.mmultimeter.Keithley2110</i> <i>method</i> ), 667	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 466
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.Attocube.anc300.ANC300</i> <i>method</i> ), 567	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 484
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.Attocube.anc350.ANC350</i> <i>method</i> ), 572	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.generic.GenericAWG</i> <i>method</i> ), 457	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 503
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.Agilent33220A</i> <i>method</i> ), 472	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.RSInstekAFG21000</i> <i>method</i> ), 490
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.Agilent33500</i> <i>method</i> ), 466	<i>set_function()</i> ( <i>pylablib.devices.AWG.specific.TektronixAFG1000</i> <i>method</i> ), 497
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2000</i> <i>method</i> ), 484	<i>set_function()</i> ( <i>pylablib.devices.Keithley.mmultimeter.Keithley2110</i> <i>method</i> ), 666
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_function()</i> ( <i>pylablib.devices.Voltcraft.mmultimeter.VC7055</i> <i>method</i> ), 981
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_function_parameters()</i> ( <i>py-</i> <i>lablib.devices.Keithley.mmultimeter.Keithley2110</i> <i>method</i> ), 667
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_gain()</i> ( <i>pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</i> <i>method</i> ), 905
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_gain_boost()</i> ( <i>py-</i> <i>lablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1026
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_gains()</i> ( <i>pylablib.devices.uc480.uc480.UC480Camera</i> <i>method</i> ), 1026
<i>set_frequency()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.InstekAFG2225</i> <i>method</i> ), 478	<i>set_gate_polarity()</i> ( <i>py-</i> <i>lablib.devices.AWG.specific.RigolDG1000</i> <i>method</i> ), 503

<i>lablib.devices.AWG.generic.GenericAWG</i> method), 458	<i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 795
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.Agilent33220A</i> method), 472	<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 804
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.Agilent33500</i> method), 466	<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 853
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.InstekAFG2000</i> method), 484	<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 847
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.InstekAFG2225</i> method), 478	<i>set_grabber_roi()</i> (py- <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 520
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.RigolDG1000</i> method), 503	<i>set_grabber_roi()</i> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowCamera</i> method), 595
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.RSInstekAFG21000</i> method), 490	<i>set_grabber_roi()</i> (py- <i>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</i> method), 586
<i>set_gate_polarity()</i> (py- <i>lablib.devices.AWG.specific.TektronixAFG1000</i> method), 497	<i>set_grabber_roi()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 647
<i>set_general_output()</i> (py- <i>lablib.devices.Trinamic.base.TMCM1110</i> method), 973	<i>set_grabber_roi()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 635
<i>set_general_output()</i> (py- <i>lablib.devices.Trinamic.base.TMCMx110</i> method), 979	<i>set_grabber_roi()</i> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</i> method), 811
<i>set_global_parameter()</i> (py- <i>lablib.devices.Trinamic.base.TMCM1110</i> method), 973	<i>set_grabber_roi()</i> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera</i> method), 795
<i>set_global_parameter()</i> (py- <i>lablib.devices.Trinamic.base.TMCMx110</i> method), 979	<i>set_grabber_roi()</i> (py- <i>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</i> method), 804
<i>set_global_speed()</i> (py- <i>lablib.devices.Arcus.performax.Performax2EXStage</i> method), 560	<i>set_grabber_roi()</i> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</i> method), 853
<i>set_global_speed()</i> (py- <i>lablib.devices.Arcus.performax.Performax4EXStage</i> method), 554	<i>set_grabber_roi()</i> (py- <i>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</i> method), 842
<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera</i> method), 520	<i>set_grating()</i> (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 545
<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQCamera</i> method), 647	<i>set_grating_offset()</i> (py- <i>lablib.devices.Andor.Shamrock.ShamrockSpectrograph</i> method), 546
<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</i> method), 634	<i>set_hardware_id()</i> (py- <i>lablib.devices.Attocube.anc350.ANC350</i> method), 571
<i>set_grabber_attribute_value()</i> (py- <i>lablib.devices.interface.camera.IGrabberAttributeCamera</i> method), 1001	<i>set_hblanking()</i> (py- <i>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</i> method), 709
<i>set_grabber_attribute_value()</i> (py-	<i>set_high_level()</i> (py- <i>lablib.devices.Cryomagnetics.base.LM500</i>



<i>method</i> ), 605		<i>method</i> ), 641	
set_high_level() lablib.devices.Cryomagnetics.base.LM510 <i>method</i> ), 611	(py-	set_image_indexing() lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera <i>method</i> ), 662	(py-
set_home_offset() lablib.devices.Thorlabs.elliptec.ElliptecMotor <i>method</i> ), 914	(py-	set_image_indexing() lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera <i>method</i> ), 656	(py-
set_horizontal_offset() lablib.devices.Tektronix.base.DPO2000 <i>method</i> ), 900	(py-	set_image_indexing() lablib.devices.interface.camera.IAttributeCamera <i>method</i> ), 1000	(py-
set_horizontal_offset() lablib.devices.Tektronix.base.ITektronixScope <i>method</i> ), 883	(py-	set_image_indexing() lablib.devices.interface.camera.IBinROICamera <i>method</i> ), 1019	(py-
set_horizontal_offset() lablib.devices.Tektronix.base.TDS2000 <i>method</i> ), 893	(py-	set_image_indexing() lablib.devices.interface.camera.ICamera <i>method</i> ), 991	(py-
set_horizontal_span() lablib.devices.Tektronix.base.DPO2000 <i>method</i> ), 900	(py-	set_image_indexing() lablib.devices.interface.camera.IExposureCamera <i>method</i> ), 1009	(py-
set_horizontal_span() lablib.devices.Tektronix.base.ITektronixScope <i>method</i> ), 883	(py-	set_image_indexing() lablib.devices.interface.camera.IGrabberAttributeCamera <i>method</i> ), 1005	(py-
set_horizontal_span() lablib.devices.Tektronix.base.TDS2000 <i>method</i> ), 893	(py-	set_image_indexing() lablib.devices.interface.camera.IROICamera <i>method</i> ), 1014	(py-
set_image_indexing() lablib.devices.AlliedVision.Bonito.BonitoIMAQCamera <i>method</i> ), 521	(py-	set_image_indexing() lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera <i>method</i> ), 713	(py-
set_image_indexing() lablib.devices.AlliedVision.Bonito.IBonitoCamera <i>method</i> ), 513	(py-	set_image_indexing() lablib.devices.PCO.SC2.PCOSC2Camera <i>method</i> ), 762	(py-
set_image_indexing() lablib.devices.Andor.AndorSDK2.AndorSDK2Camera <i>method</i> ), 533	(py-	set_image_indexing() lablib.devices.Photometrics.pvcam.PvcamCamera <i>method</i> ), 778	(py-
set_image_indexing() lablib.devices.Andor.AndorSDK3.AndorSDK3Camera <i>method</i> ), 543	(py-	set_image_indexing() lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera <i>method</i> ), 787	(py-
set_image_indexing() lablib.devices.Basler.pylon.BaslerPylonCamera <i>method</i> ), 584	(py-	set_image_indexing() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa <i>method</i> ), 811	(py-
set_image_indexing() lablib.devices.BitFlow.BitFlow.BitFlowCamera <i>method</i> ), 595	(py-	set_image_indexing() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCam <i>method</i> ), 796	(py-
set_image_indexing() lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber <i>method</i> ), 590	(py-	set_image_indexing() lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame <i>method</i> ), 804	(py-
set_image_indexing() lablib.devices.DCAM.DCAM.DCAMCamera <i>method</i> ), 621	(py-	set_image_indexing() lablib.devices.PrincetonInstruments.picam.PicamCamera <i>method</i> ), 833	(py-
set_image_indexing() lablib.devices.IMAQ.IMAQ.IMAQCamera <i>method</i> ), 647	(py-	set_image_indexing() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera <i>method</i> ), 853	(py-
set_image_indexing() lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber	(py-	set_image_indexing() lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb	(py-

method), 847

set\_image\_indexing() (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 910

set\_image\_indexing() (py-lablib.devices.uc480.uc480.UC480Camera method), 1030

set\_index\_values() (py-lablib.core.gui.widgets.button\_selector.ButtonSelector method), 233

set\_index\_values() (py-lablib.core.gui.widgets.combo\_box.ComboBox method), 234

set\_indicator() (py-lablib.core.gui.value\_handling.GUIValues method), 329

set\_indicator() (py-lablib.core.gui.widgets.container.IQContainer method), 238

set\_indicator() (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 245

set\_indicator() (py-lablib.core.gui.widgets.container.QContainer method), 240

set\_indicator() (py-lablib.core.gui.widgets.container.QDialogContainer method), 258

set\_indicator() (py-lablib.core.gui.widgets.container.QFrameContainer method), 254

set\_indicator() (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 263

set\_indicator() (py-lablib.core.gui.widgets.container.QScrollAreaContainer method), 271

set\_indicator() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainerWidget method), 268

set\_indicator() (py-lablib.core.gui.widgets.container.QTabContainer method), 274

set\_indicator() (py-lablib.core.gui.widgets.container.QWidgetContainer method), 249

set\_indicator() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 292

set\_indicator() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 305

set\_interval() (pylablib.devices.Cryomagnetics.base.LM510 method), 605

set\_interval() (pylablib.devices.Cryomagnetics.base.LM510 method), 611

set\_iris\_width() (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548

set\_limiter() (pylablib.core.gui.widgets.edit.NumEdit method), 275

set\_limiter() (pylablib.core.gui.widgets.label.NumLabel method), 278

set\_load() (pylablib.devices.AWG.generic.GenericAWG method), 456

set\_load() (pylablib.devices.AWG.specific.Agilent33220A method), 472

set\_load() (pylablib.devices.AWG.specific.Agilent33500 method), 466

set\_load() (pylablib.devices.AWG.specific.InstekAFG2000 method), 484

set\_load() (pylablib.devices.AWG.specific.InstekAFG2225 method), 478

set\_load() (pylablib.devices.AWG.specific.RigolDG1000 method), 503

set\_load() (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 490

set\_load() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 497

set\_low\_level() (py-lablib.devices.Cryomagnetics.base.LM500 method), 605

set\_low\_level() (py-lablib.devices.Cryomagnetics.base.LM510 method), 611

set\_manual\_output() (py-lablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943

set\_measurement\_filter() (py-lablib.devices.Pfeiffer.base.TPG260 method), 765

set\_measurement\_interval() (py-lablib.devices.HighFinesse.wlm.WLM method), 628

set\_measurement\_rate() (py-lablib.devices.Voltcraft.multimeter.VC7055 method), 981

set\_metadata\_mode() (py-lablib.devices.PCO.SC2.PCOSC2Camera method), 759

set\_microstep\_resolution() (py-lablib.devices.Trinamic.base.TMCM1110 method), 973

set\_microstep\_resolution() (py-lablib.devices.Trinamic.base.TMCMx110 method), 979

set\_mode() (pylablib.devices.Attocube.anc300.ANC300 method), 566

<code>set_mode()</code> (pylablib.devices.Cryomagnetics.base.LM500 method), 605	<code>set_options()</code> (pylablib.core.gui.widgets.button_selector.ButtonSelector method), 233
<code>set_mode()</code> (pylablib.devices.Cryomagnetics.base.LM510 method), 611	<code>set_options()</code> (pylablib.core.gui.widgets.combo_box.ComboBox method), 235
<code>set_mode()</code> (pylablib.devices.OZOptics.base.EPC04 method), 745	<code>set_options()</code> (pylablib.core.gui.widgets.label.EnumLabel method), 278
<code>set_mode_parameters()</code> (pylablib.devices.BitFlow.BitFlow.CameraFileEditor method), 596	<code>set_out_aux_port()</code> (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526
<code>set_modulation_power()</code> (pylablib.devices.Hubner.Cobolt.Cobolt method), 632	<code>set_out_of_range()</code> (pylablib.core.gui.widgets.button_selector.ButtonSelector method), 232
<code>set_motor_type()</code> (pylablib.devices.Newport.picomotor.Picomotor8742 method), 737	<code>set_out_of_range()</code> (pylablib.core.gui.widgets.combo_box.ComboBox method), 234
<code>set_names()</code> (pylablib.core.dataproc.table_wrap.Array2DWrapper method), 158	<code>set_output_current()</code> (pylablib.devices.Hubner.Cobolt.Cobolt method), 631
<code>set_names()</code> (pylablib.core.dataproc.table_wrap.DataFrame2DWrapper method), 160	<code>set_output_mode()</code> (pylablib.devices.Hubner.Cobolt.Cobolt method), 631
<code>set_noise_filter_mode()</code> (pylablib.devices.PCO.SC2.PCOSC2Camera method), 758	<code>set_output_mode()</code> (pylablib.devices.LighthousePhotonics.base.SproutG method), 690
<code>set_number_pixels()</code> (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548	<code>set_output_parameters()</code> (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943
<code>set_ocp_threshold()</code> (pylablib.devices.ElektroAutomatik.base.PS2000B method), 625	<code>set_output_polarity()</code> (pylablib.devices.AWG.generic.GenericAWG method), 456
<code>set_ocp_threshold()</code> (pylablib.devices.Rigol.power_supply.DP1116A method), 835	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.Agilent33220A method), 472
<code>set_offset()</code> (pylablib.devices.Attocube.anc300.ANC300 method), 567	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.Agilent33500 method), 466
<code>set_offset()</code> (pylablib.devices.Attocube.anc350.ANC350 method), 572	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.InstekAFG2000 method), 484
<code>set_offset()</code> (pylablib.devices.AWG.generic.GenericAWG method), 456	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.InstekAFG2225 method), 474
<code>set_offset()</code> (pylablib.devices.AWG.specific.Agilent33220A method), 472	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.RigolDG1000 method), 503
<code>set_offset()</code> (pylablib.devices.AWG.specific.Agilent33500 method), 466	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 491
<code>set_offset()</code> (pylablib.devices.AWG.specific.InstekAFG2000 method), 484	<code>set_output_polarity()</code> (pylablib.devices.AWG.specific.TektronixAFG1000 method), 497
<code>set_offset()</code> (pylablib.devices.AWG.specific.InstekAFG2225 method), 474	<code>set_operation_mode()</code> (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943
<code>set_offset()</code> (pylablib.devices.AWG.specific.RigolDG1000 method), 503	
<code>set_offset()</code> (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 491	
<code>set_offset()</code> (pylablib.devices.AWG.specific.TektronixAFG1000 method), 497	
<code>set_operation_mode()</code> (pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 943	



<code>set_output_power()</code> (py-lablib.devices.Hubner.Cobolt.Cobolt method), 631	<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 491
<code>set_output_power()</code> (py-lablib.devices.LaserQuantum.base.Finesse method), 683	<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 497
<code>set_output_power()</code> (py-lablib.devices.LighthousePhotonics.base.SproutG method), 691	<code>set_output_voltage()</code> (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939
<code>set_output_range()</code> (py-lablib.devices.AWG.generic.GenericAWG method), 457	<code>set_overflow_behavior()</code> (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 540
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.Agilent33220A method), 472	<code>set_ovp_threshold()</code> (py-lablib.devices.ElektroAutomatik.base.PS2000B method), 624
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.Agilent33500 method), 466	<code>set_ovp_threshold()</code> (py-lablib.devices.Rigol.power_supply.DP1116A method), 835
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.InstekAFG2000 method), 484	<code>set_pcount()</code> (pylablib.devices.Thorlabs.serial.FW method), 958
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.InstekAFG2225 method), 478	<code>set_phase()</code> (pylablib.devices.AWG.generic.GenericAWG method), 457
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.RigolDG1000 method), 503	<code>set_phase()</code> (pylablib.devices.AWG.specific.Agilent33220A method), 472
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.RSInstekAFG21000 method), 491	<code>set_phase()</code> (pylablib.devices.AWG.specific.Agilent33500 method), 466
<code>set_output_range()</code> (py-lablib.devices.AWG.specific.TektronixAFG1000 method), 497	<code>set_phase()</code> (pylablib.devices.AWG.specific.InstekAFG2000 method), 485
<code>set_output_range()</code> (py-lablib.devices.Rigol.power_supply.DP1116A method), 834	<code>set_phase()</code> (pylablib.devices.AWG.specific.InstekAFG2225 method), 478
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.generic.GenericAWG method), 460	<code>set_phase()</code> (pylablib.devices.AWG.specific.RigolDG1000 method), 503
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.Agilent33220A method), 472	<code>set_phase()</code> (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 491
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.Agilent33500 method), 466	<code>set_phase()</code> (pylablib.devices.AWG.specific.TektronixAFG1000 method), 497
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.InstekAFG2000 method), 485	<code>set_pid_parameters()</code> (py-lablib.devices.Thorlabs.kinesis.KinesisQuadDetector method), 942
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.InstekAFG2225 method), 478	<code>set_piezoet_ctl_status()</code> (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
<code>set_output_trigger_slope()</code> (py-lablib.devices.AWG.specific.RigolDG1000 method), 503	<code>set_piezoet_drive_params()</code> (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 859
	<code>set_piezoet_feedback_params()</code> (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 859
	<code>set_piezoet_feedforward_params()</code> (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 859
	<code>set_piezoet_position()</code> (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 859

`set_pixel_clock()` (pylablib.devices.Mightex.MightexSSeries.MightexSSeries method), 935  
`set_position_reference()` (pylablib.devices.Trinamic.base.TMCM1110 method), 709  
`set_pixel_rate()` (pylablib.devices.PCO.SC2.PCOS2Camera method), 973  
`set_position_reference()` (pylablib.devices.Trinamic.base.TMCMx110 method), 757  
`set_pixel_rate()` (pylablib.devices.uc480.uc480.UC480Camera method), 979  
`set_position_upper_limit()` (pylablib.devices.PhysikInstrumente.base.PIE515 method), 1026  
`set_position_upper_limit()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 821  
`set_pixel_width()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548  
`set_points_number()` (pylablib.devices.Tektronix.base.DPO2000 method), 817  
`set_points_number()` (pylablib.devices.Tektronix.base.ITektronixScope method), 900  
`set_points_number()` (pylablib.devices.Tektronix.base.TDS2000 method), 884  
`set_position()` (pylablib.devices.Thorlabs.serial.FW method), 893  
`set_position()` (pylablib.devices.Thorlabs.serial.FWv1 method), 958  
`set_position_lower_limit()` (pylablib.devices.PhysikInstrumente.base.PIE515 method), 961  
`set_position_lower_limit()` (pylablib.devices.PhysikInstrumente.base.PIE516 method), 820  
`set_position_reference()` (pylablib.devices.Arcus.performax.Performax2EXStage method), 893  
`set_position_reference()` (pylablib.devices.Arcus.performax.Performax4EXStage method), 900  
`set_position_reference()` (pylablib.devices.Arcus.performax.PerformaxDMXJSASStage method), 884  
`set_position_reference()` (pylablib.devices.Newport.picomotor.Picomotor8742 method), 884  
`set_position_reference()` (pylablib.devices.SmarAct.MCS2.MCS2 method), 884  
`set_position_reference()` (pylablib.devices.Standa.base.Standa8SMC method), 878  
`set_position_reference()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 929  
`set_position_reference()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 929  
`set_pulse_mode()` (pylablib.devices.HighFinesse.wlm.WLM method), 628  
`set_pulse_output()` (pylablib.devices.NI.daq.NIDAQ method), 724  
`set_pulse_width()` (pylablib.devices.AWG.generic.GenericAWG method), 457  
`set_pulse_width()` (pylablib.devices.AWG.specific.Agilent33220A method), 472  
`set_pulse_width()` (pylablib.devices.AWG.specific.Agilent33500 method), 466  
`set_pulse_width()` (pylablib.devices.AWG.specific.InstekAFG2000 method), 485  
`set_pulse_width()` (pylablib.devices.AWG.specific.InstekAFG2225 method), 479  
`set_pulse_width()` (pylablib.devices.AWG.specific.RigolDG1000 method), 479

- method*), 503
- `set_pulse_width()` (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 491
- `set_pulse_width()` (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 492
- `set_ramp_symmetry()` (py-lablib.devices.AWG.generic.GenericAWG *method*), 457
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.Agilent33220A *method*), 472
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.Agilent33500 *method*), 466
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.InstekAFG2000 *method*), 485
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.InstekAFG2225 *method*), 479
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.RigolDG1000 *method*), 503
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.RSInstekAFG21000 *method*), 491
- `set_ramp_symmetry()` (py-lablib.devices.AWG.specific.TektronixAFG1000 *method*), 497
- `set_range()` (pylablib.devices.Ophir.base.VegaPowerMeter *method*), 752
- `set_range()` (pylablib.devices.Thorlabs.misc.GenericPM *method*), 947
- `set_range()` (pylablib.devices.Thorlabs.misc.PM160 *method*), 953
- `set_range()` (pylablib.devices.Voltcraft.mmultimeter.VC7055 *method*), 981
- `set_range_idx()` (py-lablib.devices.Ophir.base.VegaPowerMeter *method*), 752
- `set_range_limit()` (py-lablib.devices.SmarAct.MCS2.MCS2 *method*), 871
- `set_read_mode()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 528
- `set_read_mode()` (py-lablib.devices.HighFinesse.wlm.WLM *method*), 626
- `set_readout_mode()` (py-lablib.devices.Photometrics.pvcam.PvcamCamera *method*), 773
- `set_readout_speed()` (py-lablib.devices.DCAM.DCAM.DCAMCamera *method*), 616
- `set_refcell_position()` (py-lablib.devices.Sirah.Matisse.SirahMatisse *method*), 860
- `set_refcell_waveform_params()` (py-lablib.devices.Sirah.Matisse.SirahMatisse *method*), 860
- `set_reg()` (pylablib.devices.Lumel.base.LumelRE72Controller *method*), 692
- `set_reg()` (pylablib.devices.Omron.base.OmronE5xCController *method*), 747
- `set_register()` (pylablib.devices.NKT.interbus.GenericInterbusModule *method*), 729
- `set_register()` (pylablib.devices.NKT.interbus.IInterbusModule *method*), 727
- `set_register()` (pylablib.devices.NKT.interbus.SuperKExtremeInterbusModule *method*), 730
- `set_register()` (pylablib.devices.NKT.interbus.SuperKFrontPanelInterbusModule *method*), 731
- `set_register()` (pylablib.devices.NKT.interbus.SuperKSelectDriverInterbusModule *method*), 732
- `set_register()` (pylablib.devices.NKT.interbus.SuperKSelectInterbusModule *method*), 733
- `set_relay()` (pylablib.devices.Conrad.base.RelayBoard *method*), 598
- `set_relay_setpoints()` (py-lablib.devices.KJL.base.KJL300 *method*), 664
- `set_roi()` (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera *method*), 521
- `set_roi()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera *method*), 508
- `set_roi()` (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera *method*), 529
- `set_roi()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera *method*), 540
- `set_roi()` (pylablib.devices.Basler.pylon.BaslerPylonCamera *method*), 579
- `set_roi()` (pylablib.devices.BitFlow.BitFlow.BitFlowCamera *method*), 595
- `set_roi()` (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber *method*), 586
- `set_roi()` (pylablib.devices.DCAM.DCAM.DCAMCamera *method*), 617
- `set_roi()` (pylablib.devices.IMAQ.IMAQ.IMAQCamera *method*), 647
- `set_roi()` (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber *method*), 635
- `set_roi()` (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera *method*), 662
- `set_roi()` (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera *method*), 652

`set_roi()` (pylablib.devices.interface.camera.IBinROICamera method), 295  
`method`), 1015 `set_row_stretch()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 245  
`set_roi()` (pylablib.devices.interface.camera.IROICamera method), 1010 `lablib.core.gui.widgets.param_table.StatusTable method`), 305  
`set_roi()` (pylablib.devices.Mightex.MightexSSeries.MightexSSeries method), 709 `set_scan_params()` (pylablib.devices.Thorlabs.elliptec.ElliptecMotor method), 914  
`set_roi()` (pylablib.devices.PCO.SC2.PCOSC2Camera method), 758 `lablib.devices.Sirah.Matisse.SirahMatisse method`), 861  
`set_roi()` (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 774 `set_scan_position()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocus method), 783 `set_sensor_curve_index()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 812 `set_sensor_kind()` (pylablib.devices.Sirah.Matisse.SirahMatisse method), 860  
`set_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 796 `set_sensor_mode()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 673  
`set_roi()` (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocus method), 804 `set_sensor_mode()` (pylablib.devices.Cryocon.base.Cryocon1x method), 600  
`set_roi()` (pylablib.devices.PrincetonInstruments.picam.Picam method), 829 `set_sensor_mode()` (pylablib.devices.Thorlabs.misc.GenericPM method), 946  
`set_roi()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware method), 853 `set_sensor_mode()` (pylablib.devices.Thorlabs.misc.PM160 method), 953  
`set_roi()` (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftware method), 842 `set_sensor_mode()` (pylablib.devices.Thorlabs.serial.FW method), 958  
`set_roi()` (pylablib.devices.Thorlabs.TLCamera.Thorlabs method), 907 `set_sensor_type()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 672  
`set_roi()` (pylablib.devices.uc480.uc480.UC480Camera method), 1027 `set_sensor_voltage()` (pylablib.devices.Attocube.anc350.ANC350 method), 571  
`set_row_stretch()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 245 `set_serial_parameter()` (pylablib.devices.AlliedVision.Bonito.Bonito method), 521  
`set_row_stretch()` (pylablib.core.gui.widgets.container.QDialogContainer method), 259 `set_serial_parameter()` (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 521  
`set_row_stretch()` (pylablib.core.gui.widgets.container.QFrameContainer method), 254 `set_setpointi()` (pylablib.devices.Lumel.base.LumelRE72Controller method), 693  
`set_row_stretch()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 263 `set_setpointi()` (pylablib.devices.Omron.base.OmronE5xCController method), 747  
`set_row_stretch()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 268 `set_shutter()` (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 538  
`set_row_stretch()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 249 `set_shutter()` (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 547  
`set_row_stretch()` (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 281 `set_shutter()` (pylablib.devices.LaserQuantum.base.Finesse method), 683  
`set_row_stretch()` (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 283 `set_shutter()` (pylablib.devices.LaserQuantum.base.Finesse method), 683  
`set_row_stretch()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 283



`set_single_value()` (py- method), 928  
`lablib.core.gui.value_handling.CheckboxValueHandle.set_switch_polarity()` (py- method), 320  
`lablib.devices.Trinamic.base.TMCM1110`  
`set_single_value()` (py- method), 974  
`lablib.core.gui.value_handling.ComboBoxValueHandle.set_switch_polarity()` (py- method), 323  
`lablib.devices.Trinamic.base.TMCMx110`  
`set_single_value()` (py- method), 979  
`lablib.core.gui.value_handling.IBoolValueHandle.set_switcher_mode()` (py- method), 319  
`lablib.devices.HighFinesse.wlm.WLM` method), 627  
`set_single_value()` (py- method), 524  
`lablib.core.gui.value_handling.ISingleValueHandle.set_temperature()` (py- method), 316  
`lablib.devices.Andor.AndorSDK2.AndorSDK2Camera`  
`set_single_value()` (py- method), 524  
`lablib.core.gui.value_handling.LabelValueHandle.set_temperature()` (py- method), 318  
`lablib.devices.Andor.AndorSDK3.AndorSDK3Camera`  
`set_single_value()` (py- method), 538  
`lablib.core.gui.value_handling.LineEditValueHandle.set_temperature()` (py- method), 317  
`lablib.devices.Photometrics.pvcam.PvcamCamera`  
`set_single_value()` (py- method), 773  
`lablib.core.gui.value_handling.ProgressBarValueHandle.set_timeout()` (py- method), 324  
`lablib.devices.Sirah.Matisse.SirahMatisse`  
`set_single_value()` (py- method), 858  
`lablib.core.gui.value_handling.PushButtonValueHandle.set_timeout()` (py- method), 321  
`lablib.devices.Sirah.Matisse.SirahMatisse`  
`set_single_value()` (py- method), 858  
`lablib.core.gui.value_handling.ToolButtonValueHandle.set_timeout()` (pylablib.core.devio.comm\_backend.FT232DeviceBackend method), 322  
`lablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 179  
`set_slit_width()` (py- method), 187  
`lablib.devices.Andor.Shamrock.ShamrockSpectrograph` method), 546  
`set_slowpiezo_ctl_params()` (py- method), 171  
`lablib.devices.Sirah.Matisse.SirahMatisse` method), 859  
`set_slowpiezo_ctl_status()` (py- method), 182  
`lablib.devices.Sirah.Matisse.SirahMatisse` method), 859  
`set_slowpiezo_position()` (py- method), 191  
`lablib.devices.Sirah.Matisse.SirahMatisse` method), 859  
`set_span()` (pylablib.devices.KJL.base.KJL300 method), 664  
`set_speed_mode()` (py- method), 195  
`lablib.devices.Thorlabs.serial.FW` method), 958  
`set_status_line_mode()` (py- method), 430  
`lablib.devices.PCO.SC2.PCOS2Camera` method), 759  
`set_styles()` (pylablib.core.gui.widgets.label.EnumLabel method), 278  
`set_timeout()` (pylablib.devices.M2.base.ICEBlocDevice method), 696  
`set_subsampling()` (py- method), 700  
`lablib.devices.uc480.uc480.UC480Camera` method), 1027  
`set_timeout()` (pylablib.devices.M2.solstis.Solstis method), 707  
`set_supported_channels()` (py- method), 707  
`lablib.devices.Thorlabs.kinesis.KinesisMotor` `set_trigger_input()` (py-

<code>lablib.devices.Attocube.anc300.ANC300</code> <code>method</code> ), 568	<code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> <code>method</code> ), 905
<code>set_trigger_interleave()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 783	<code>(py- set_trigger_mode()</code> <code>lablib.devices.uc480.uc480.UC480Camera</code> <code>method</code> ), 1025
<code>set_trigger_interleave()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlipper</code> <code>method</code> ), 812	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 458
<code>set_trigger_interleave()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</code> <code>method</code> ), 796	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 473
<code>set_trigger_interleave()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> <code>method</code> ), 804	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 466
<code>set_trigger_level()</code> <code>lablib.devices.Tektronix.base.DPO2000</code> <code>method</code> ), 900	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 485
<code>set_trigger_level()</code> <code>lablib.devices.Tektronix.base.ITektronixScope</code> <code>method</code> ), 882	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 479
<code>set_trigger_level()</code> <code>lablib.devices.Tektronix.base.TDS2000</code> <code>method</code> ), 893	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 503
<code>set_trigger_mode()</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 526	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 491
<code>set_trigger_mode()</code> <code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> <code>method</code> ), 538	<code>(py- set_trigger_slope()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 497
<code>set_trigger_mode()</code> <code>lablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 616	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 458
<code>set_trigger_mode()</code> <code>lablib.devices.PCO.SC2.PCOSC2Camera</code> <code>method</code> ), 756	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 473
<code>set_trigger_mode()</code> <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 774	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 467
<code>set_trigger_mode()</code> <code>lablib.devices.Tektronix.base.DPO2000</code> <code>method</code> ), 900	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 485
<code>set_trigger_mode()</code> <code>lablib.devices.Tektronix.base.ITektronixScope</code> <code>method</code> ), 882	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 479
<code>set_trigger_mode()</code> <code>lablib.devices.Tektronix.base.TDS2000</code> <code>method</code> ), 893	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 503
<code>set_trigger_mode()</code> <code>lablib.devices.Thorlabs.serial.FW</code> <code>method</code> ), 958	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 491
<code>set_trigger_mode()</code> <code>lablib.devices.Thorlabs.serial.FWv1</code> <code>method</code> ), 961	<code>(py- set_trigger_source()</code> <code>lablib.devices.AWG.generic.GenericAWG</code> <code>method</code> ), 497
<code>set_trigger_mode()</code>	<code>(py- set_tune_units()</code>

- `pylablib.devices.Sirah.tuner.MatisseTuner`  
method), 864
- `set_turret()` (`pylablib.devices.Andor.Shamrock.ShamrockSDK3`  
method), 546
- `set_units()` (`pylablib.devices.Agilent.pressure.XGS600`  
method), 506
- `set_units()` (`pylablib.devices.Leybold.base.ITR90`  
method), 687
- `set_units()` (`pylablib.devices.Pfeiffer.base.TPG260`  
method), 764
- `set_value()` (`pylablib.core.gui.value_handling.CheckboxValueHandler`  
method), 320
- `set_value()` (`pylablib.core.gui.value_handling.ComboBoxValueHandler`  
method), 323
- `set_value()` (`pylablib.core.gui.value_handling.GUIValueSetter`  
method), 329
- `set_value()` (`pylablib.core.gui.value_handling.IBoolValueSetter`  
method), 319
- `set_value()` (`pylablib.core.gui.value_handling.IIndicatorHandler`  
method), 325
- `set_value()` (`pylablib.core.gui.value_handling.ISingleValueSetter`  
method), 316
- `set_value()` (`pylablib.core.gui.value_handling.IValueHandler`  
method), 311
- `set_value()` (`pylablib.core.gui.value_handling.LabelIndicator`  
method), 326
- `set_value()` (`pylablib.core.gui.value_handling.LabelValueSetter`  
method), 318
- `set_value()` (`pylablib.core.gui.value_handling.LineEditValueHandler`  
method), 317
- `set_value()` (`pylablib.core.gui.value_handling.ProgressBaseValueSetter`  
method), 324
- `set_value()` (`pylablib.core.gui.value_handling.PropertyValueSetter`  
method), 314
- `set_value()` (`pylablib.core.gui.value_handling.PushButtonValueHandler`  
method), 321
- `set_value()` (`pylablib.core.gui.value_handling.StandardIndicatorValueHandler`  
method), 325
- `set_value()` (`pylablib.core.gui.value_handling.StandardValueHandler`  
method), 315
- `set_value()` (`pylablib.core.gui.value_handling.ToolButtonValueHandler`  
method), 322
- `set_value()` (`pylablib.core.gui.value_handling.VirtualValueHandler`  
method), 313
- `set_value()` (`pylablib.core.gui.widgets.button.ToggleButton`  
method), 232
- `set_value()` (`pylablib.core.gui.widgets.button_selector.BusSelector`  
method), 233
- `set_value()` (`pylablib.core.gui.widgets.combo_box.ComboBox`  
method), 235
- `set_value()` (`pylablib.core.gui.widgets.container.IQContainer`  
method), 238
- `set_value()` (`pylablib.core.gui.widgets.container.IQWidgetContainer`  
method), 245
- `set_value()` (`pylablib.core.gui.widgets.container.QContainer`  
method), 240
- `set_value()` (`pylablib.core.gui.widgets.container.QDialogContainer`  
method), 259
- `set_value()` (`pylablib.core.gui.widgets.container.QFrameContainer`  
method), 254
- `set_value()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer`  
method), 263
- `set_value()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer`  
method), 271
- `set_value()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainer`  
method), 268
- `set_value()` (`pylablib.core.gui.widgets.container.QTabContainer`  
method), 274
- `set_value()` (`pylablib.core.gui.widgets.container.QWidgetContainer`  
method), 249
- `set_value()` (`pylablib.core.gui.widgets.edit.NumEdit`  
method), 277
- `set_value()` (`pylablib.core.gui.widgets.edit.TextEdit`  
method), 275
- `set_value()` (`pylablib.core.gui.widgets.label.EnumLabel`  
method), 278
- `set_value()` (`pylablib.core.gui.widgets.label.NumLabel`  
method), 279
- `set_value()` (`pylablib.core.gui.widgets.label.TextLabel`  
method), 277
- `set_value()` (`pylablib.core.gui.widgets.param_table.ParamTable`  
method), 291
- `set_value()` (`pylablib.core.gui.widgets.param_table.StatusTable`  
method), 305
- `set_value()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute`  
method), 535
- `set_value()` (`pylablib.devices.Attocube.anc350.ANC350`  
method), 570
- `set_value()` (`pylablib.devices.Basler.pylon.BaslerPylonAttribute`  
method), 577
- `set_value()` (`pylablib.devices.DCAM.DCAM.DCAMAttribute`  
method), 615
- `set_value()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute`  
method), 650
- `set_value()` (`pylablib.devices.Photometrics.pvcam.PvcamAttribute`  
method), 771
- `set_value()` (`pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute`  
method), 781
- `set_value()` (`pylablib.devices.PrincetonInstruments.picam.PicamAttribute`  
method), 827
- `set_value()` (`pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute`  
method), 840
- `set_value_labels()` (`pylablib.core.gui.widgets.button.ToggleButton`  
method), 232
- `set_variable()` (`pylablib.core.thread.controller.QTaskThread`  
method), 360
- `set_variable()` (`pylablib.core.thread.controller.QThreadController`  
method), 360

- method), 346
- set\_variable() (pylablib.core.utils.ipc.SharedMemIPCTable method), 436
- set\_vcr\_function\_parameters() (pylablib.devices.Keithley.multimeter.Keithley2110 method), 667
- set\_velocity() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817
- set\_velocity() (pylablib.devices.Thorlabs.elliptec.Elliptec4100 method), 914
- set\_vertical\_position() (pylablib.devices.Tektronix.base.DPO2000 method), 900
- set\_vertical\_position() (pylablib.devices.Tektronix.base.ITektronixScope method), 883
- set\_vertical\_position() (pylablib.devices.Tektronix.base.TDS2000 method), 893
- set\_vertical\_span() (pylablib.devices.Tektronix.base.DPO2000 method), 900
- set\_vertical\_span() (pylablib.devices.Tektronix.base.ITektronixScope method), 883
- set\_vertical\_span() (pylablib.devices.Tektronix.base.TDS2000 method), 893
- set\_visible() (pylablib.core.gui.widgets.param\_table.ParamTable method), 291
- set\_visible() (pylablib.core.gui.widgets.param\_table.StateTable method), 305
- set\_voltage() (pylablib.devices.Attocube.anc300.ANC300 method), 567
- set\_voltage() (pylablib.devices.Attocube.anc350.ANC350 method), 572
- set\_voltage() (pylablib.devices.ElektroAutomatik.base.PS2000 method), 624
- set\_voltage() (pylablib.devices.OZOptics.base.EPC04 method), 744
- set\_voltage() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 820
- set\_voltage() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 816
- set\_voltage() (pylablib.devices.Rigol.power\_supply.DP1116A method), 834
- set\_voltage() (pylablib.devices.Thorlabs.serial.MDT69xA method), 964
- set\_voltage\_lower\_limit() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 820
- set\_voltage\_lower\_limit() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817
- set\_voltage\_outputs() (pylablib.devices.NI.daq.NIDAQ method), 722
- set\_voltage\_pattern() (pylablib.devices.Attocube.anc300.ANC300 method), 567
- set\_voltage\_range() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939
- set\_voltage\_source() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 939
- set\_voltage\_upper\_limit() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 820
- set\_voltage\_upper\_limit() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817
- set\_vsspeed() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 525
- set\_wait\_callback() (pylablib.core.utils.net.ClientSocket method), 442
- set\_waveform() (pylablib.devices.OZOptics.base.EPC04 method), 745
- set\_wavelength() (pylablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 546
- set\_wavelength() (pylablib.devices.Ophir.base.VegaPowerMeter method), 752
- set\_wavelength() (pylablib.devices.OZOptics.base.TF100 method), 741
- set\_wavelength() (pylablib.devices.Thorlabs.misc.GenericPM method), 947
- set\_wavelength() (pylablib.devices.Thorlabs.misc.PM160 method), 953
- set\_wavelength\_correction() (pylablib.devices.OZOptics.base.TF100 method), 741
- set\_white\_balance\_matrix() (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 904
- set\_xarg\_name() (pylablib.core.dataproc.fitting.Fitter method), 141
- set\_zero() (pylablib.devices.KJL.base.KJL300 method), 664
- setattr\_call() (in module pylablib.core.utils.functions), 423
- setbp() (in module pylablib), 1034
- setbp() (in module pylablib.core.utils.general), 432
- setdefault() (pylablib.core.utils.dictionary.Dictionary



method), 379

setdefault() (pylablib.core.utils.dictionary.DictionaryPointer method), 392

setdefault() (pylablib.core.utils.dictionary.FilterTree method), 409

setdefault() (pylablib.core.utils.dictionary.ItemAccessor method), 412

setdefault() (pylablib.core.utils.dictionary.PrefixTree method), 401

setpoint (pylablib.devices.Sirah.Matisse.TFastpiezoCtlParameters attribute), 856

setpoint (pylablib.devices.Sirah.Matisse.TSlowpiezoCtlParameters attribute), 855

setpoint (pylablib.devices.Sirah.Matisse.TThinnetCtlParameters attribute), 855

settle\_time (pylablib.devices.Lakeshore.base.TLakeshore370Filter attribute), 677

setup() (pylablib.core.gui.widgets.container.IQContainer method), 236

setup() (pylablib.core.gui.widgets.container.IQWidgetContainer method), 241

setup() (pylablib.core.gui.widgets.container.QContainer method), 240

setup() (pylablib.core.gui.widgets.container.QDialogContainer method), 259

setup() (pylablib.core.gui.widgets.container.QFrameContainer method), 254

setup() (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 260

setup() (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 269

setup() (pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainer method), 268

setup() (pylablib.core.gui.widgets.container.QTabContainer method), 274

setup() (pylablib.core.gui.widgets.container.QWidgetContainer method), 249

setup() (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 279

setup() (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 283

setup() (pylablib.core.gui.widgets.param\_table.ParamTable method), 284

setup() (pylablib.core.gui.widgets.param\_table.StatusTable method), 295

setup() (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 904

setup\_accum\_mode() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 527

setup\_acquisition() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 521

setup\_acquisition() (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 508

setup\_acquisition() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 530

setup\_acquisition() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 539

setup\_acquisition() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 580

setup\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 595

setup\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 587

setup\_acquisition() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 617

setup\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 647

setup\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 637

setup\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera method), 662

setup\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 651

setup\_acquisition() (pylablib.devices.interface.camera.IAttributeCamera method), 1000

setup\_acquisition() (pylablib.devices.interface.camera.IBinROICamera method), 1019

setup\_acquisition() (pylablib.devices.interface.camera.ICamera method), 990

setup\_acquisition() (pylablib.devices.interface.camera.IExposureCamera method), 1009

setup\_acquisition() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1005

setup\_acquisition() (pylablib.devices.interface.camera.IROICamera method), 1014

setup\_acquisition() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 710

setup\_acquisition() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1005

<code>lablib.devices.PCO.SC2.PCOSC2Camera</code> method), 757	<code>lablib.devices.Lakeshore.base.Lakeshore370</code> method), 678
<code>setup_acquisition()</code> <code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> method), 775	<code>setup_cl_move()</code> <code>lablib.devices.SmarAct.MCS2.MCS2</code> method), 870
<code>setup_acquisition()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> method), 787	<code>setup_clock()</code> ( <code>pylablib.devices.NI.daq.NIDAQ</code> method), 719
<code>setup_acquisition()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 806	<code>setup_cont_mode()</code> ( <code>py-</code> <code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> method), 728
<code>setup_acquisition()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera</code> method), 796	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.FT232DeviceBackend</code> method), 180
<code>setup_acquisition()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> method), 804	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.HIDeviceBackend</code> method), 188
<code>setup_acquisition()</code> <code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> method), 829	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.IDeviceCommBackend</code> method), 171
<code>setup_acquisition()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> method), 854	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.NetworkDeviceBackend</code> method), 183
<code>setup_acquisition()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 843	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.PyUSBDeviceBackend</code> method), 186
<code>setup_acquisition()</code> <code>lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> method), 906	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.RecordedDeviceBackend</code> method), 191
<code>setup_acquisition()</code> <code>lablib.devices.uc480.uc480.UC480Camera</code> method), 1026	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.SerialDeviceBackend</code> method), 177
<code>setup_analog_output()</code> <code>lablib.devices.Lakeshore.base.Lakeshore218</code> method), 673	<code>setup_cooldown()</code> ( <code>py-</code> <code>lablib.core.devio.comm_backend.VisaDeviceBackend</code> method), 174
<code>setup_analog_output()</code> <code>lablib.devices.Lakeshore.base.Lakeshore370</code> method), 678	<code>setup_current()</code> ( <code>py-</code> <code>lablib.devices.Trinamic.base.TMCM1110</code> method), 973
<code>setup_autocalibration()</code> <code>lablib.devices.HighFinesse.wlm.WLM</code> method), 629	<code>setup_current()</code> ( <code>py-</code> <code>lablib.devices.Trinamic.base.TMCMx110</code> method), 979
<code>setup_averaging()</code> <code>lablib.devices.Keithley.multimeter.Keithley2110</code> method), 668	<code>setup_drive()</code> ( <code>pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor</code> method), 935
<code>setup_camlink_pixel_format()</code> <code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> method), 804	<code>setup_edge_trigger()</code> ( <code>py-</code> <code>lablib.devices.Tektronix.base.DPO2000</code> method), 900
<code>setup_camlink_pixel_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 854	<code>setup_edge_trigger()</code> ( <code>py-</code> <code>lablib.devices.Tektronix.base.ITektronixScope</code> method), 882
<code>setup_camlink_pixel_format()</code> <code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 843	<code>setup_edge_trigger()</code> ( <code>py-</code> <code>lablib.devices.Tektronix.base.TDS2000</code> method), 894
<code>setup_channel_range()</code>	<code>setup_edge_trigger()</code> ( <code>py-</code> <code>lablib.devices.Newport.picomotor.Picomotor8742</code> method), 737

`setup_ext_trigger()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 974  
`setup_ext_trigger()` (py-lablib.devices.DCAM.DCAM.DCAMCamera method), 527  
`setup_ext_trigger()` (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 616  
`setup_ext_trigger()` (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 782  
`setup_ext_trigger()` (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 905  
`setup_fast_kinetic_mode()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 812  
`setup_filter()` (pylablib.devices.Lakeshore.base.Lakeshore218 method), 529  
`setup_filter()` (pylablib.devices.Lakeshore.base.Lakeshore370 method), 674  
`setup_flipper()` (py-lablib.devices.Thorlabs.kinesis.MFF method), 679  
`setup_func()` (in module py-lablib.core.utils.ctypes\_wrap), 372  
`setup_gauge_control()` (py-lablib.devices.Pfeiffer.base.TPG260 method), 925  
`setup_gen_move()` (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 766  
`setup_home()` (pylablib.devices.Trinamic.base.TMCM1110 method), 931  
`setup_home()` (pylablib.devices.Trinamic.base.TMCMx110 method), 974  
`setup_homing()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 979  
`setup_image_mode()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 931  
`setup_jog()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 529  
`setup_jog()` (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 930  
`setup_kcube_trigio()` (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 936  
`setup_kcube_trigpos()` (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 931  
`setup_kinetic_mode()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 931  
`setup_limit_switch()` (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 527  
`setup_limit_switches()` (py-lablib.devices.Trinamic.base.TMCM1110 method), 931  
`setup_limit_switches()` (py-lablib.devices.Trinamic.base.TMCMx110 method), 974  
`setup_max_baudrate()` (py-lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera method), 796  
`setup_max_baudrate()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera method), 812  
`setup_max_baudrate()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 796  
`setup_max_baudrate()` (py-lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera method), 805  
`setup_move()` (pylablib.devices.Standa.base.Standa8SMC method), 879  
`setup_multi_track_mode()` (py-lablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 529  
`setup_name()` (pylablib.core.gui.widgets.container.IQContainer method), 236  
`setup_name()` (pylablib.core.gui.widgets.container.IQWidgetContainer method), 245  
`setup_name()` (pylablib.core.gui.widgets.container.QContainer method), 240  
`setup_name()` (pylablib.core.gui.widgets.container.QDialogContainer method), 259  
`setup_name()` (pylablib.core.gui.widgets.container.QFrameContainer method), 254  
`setup_name()` (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 263  
`setup_name()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 271  
`setup_name()` (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 268  
`setup_name()` (pylablib.core.gui.widgets.container.QTabContainer method), 274  
`setup_name()` (pylablib.core.gui.widgets.container.QWidgetContainer method), 250  
`setup_name()` (pylablib.core.gui.widgets.param\_table.ParamTable method), 295  
`setup_name()` (pylablib.core.gui.widgets.param\_table.StatusTable method), 305  
`setup_pixel_correction()` (py-lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera method), 905  
`setup_pixels_from_camera()` (py-lablib.devices.Andor.Shamrock.ShamrockSpectrograph method), 548  
`setup_polctl()` (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 932  
`setup_power()` (pylablib.devices.Standa.base.Standa8SMC method), 879

method), 879

setup\_random\_track\_mode() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 529

setup\_scan\_move() (pylablib.devices.SmarAct.MCS2.MCS2 method), 871

setup\_serial\_params() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 521

setup\_serial\_params() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 647

setup\_serial\_params() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 636

setup\_serial\_params() (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera method), 796

setup\_shutter() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 526

setup\_single\_track\_mode() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 529

setup\_step\_move() (pylablib.devices.SmarAct.MCS2.MCS2 method), 870

setup\_switch() (pylablib.devices.Pfeiffer.base.TPG260 method), 765

setup\_task() (pylablib.core.thread.controller.QTaskThread method), 353

setup\_terascan() (pylablib.devices.M2.emm.EMM method), 698

setup\_terascan() (pylablib.devices.M2.solstis.Solstis method), 703

setup\_velocity() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 738

setup\_velocity() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 930

setup\_velocity() (pylablib.devices.Trinamic.base.TMCM1110 method), 975

setup\_velocity() (pylablib.devices.Trinamic.base.TMCMx110 method), 979

setup\_voltage\_output\_clock() (pylablib.devices.NI.daq.NIDAQ method), 723

sfglob() (in module pylablib.core.utils.string), 450

sfregex() (in module pylablib.core.utils.string), 450

ShamrockSpectrograph (class in pylablib.devices.Andor.Shamrock), 545

shape() (pylablib.core.dataproc.table\_wrap.Array1DWrapper method), 154

shape() (pylablib.core.dataproc.table\_wrap.Array2DWrapper method), 159

shape() (pylablib.core.dataproc.table\_wrap.DataFrame2DWrapper method), 161

shape() (pylablib.core.dataproc.table\_wrap.I1DWrapper method), 153

shape() (pylablib.core.dataproc.table\_wrap.I2DWrapper method), 157

shape() (pylablib.core.dataproc.table\_wrap.IGenWrapper method), 152

shape() (pylablib.core.dataproc.table\_wrap.Series1DWrapper method), 156

SharedMemIPCChannel (class in pylablib.core.utils.ipc), 435

SharedMemIPCTable (class in pylablib.core.utils.ipc), 435

shift() (pylablib.core.dataproc.ctransform\_fallback.CLinear2DTransform method), 134

shifted() (pylablib.core.dataproc.transform.Indexed2DTransform method), 162

shifted() (pylablib.core.dataproc.transform.LinearTransform method), 161

show\_value() (pylablib.core.gui.widgets.edit.NumEdit method), 277

show\_value() (pylablib.core.gui.widgets.edit.TextEdit method), 275

shutdown() (pylablib.devices.Andor.AndorSDK2.LibraryController method), 522

shutdown() (pylablib.devices.Andor.AndorSDK3.LibraryController method), 534

shutdown() (pylablib.devices.Andor.Shamrock.LibraryController method), 544

shutdown() (pylablib.devices.Basler.pylon.LibraryController method), 575

shutdown() (pylablib.devices.DCAM.DCAM.LibraryController method), 613

shutdown() (pylablib.devices.Mightex.MightexSSeries.LibraryController method), 708

shutdown() (pylablib.devices.Photometrics.pvcam.LibraryController method), 769

shutdown() (pylablib.devices.PhotonFocus.PhotonFocus.LibraryController method), 779

shutdown() (pylablib.devices.PrincetonInstruments.picam.LibraryController method), 824

shutdown() (pylablib.devices.SmarAct.MCS2.LibraryController method), 868

shutdown() (pylablib.devices.SmarAct.scu3d.LibraryController method), 873

shutdown() (pylablib.devices.Thorlabs.TLCAmber.LibraryController method), 902

shutdown() (pylablib.devices.utils.load\_lib.LibraryController method), 1033



signature() (pylablib.core.utils.functions.FunctionSignature method), 460

SilenceException (class in pylablib.core.utils.general), 428

SiliconSoftwareCamera (class in pylablib.devices.SiliconSoftware.fgrab), 848

SiliconSoftwareCamera.BufferManager (class in pylablib.devices.SiliconSoftware.fgrab), 848

SiliconSoftwareFrameGrabber (class in pylablib.devices.SiliconSoftware.fgrab), 841

SiliconSoftwareFrameGrabber.BufferManager (class in pylablib.devices.SiliconSoftware.fgrab), 843

single\_op() (pylablib.core.devio.comm\_backend.FT232RLBackend method), 179

single\_op() (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 176

SingleFileSystemDataLocation (class in pylablib.core.fileio.location), 220

SirahMatisse (class in pylablib.devices.Sirah.Matisse), 856

size (pylablib.core.utils.ipc.TShmemVarDesc attribute), 436

size (pylablib.devices.Andor.AndorSDK3.TFrameInfo attribute), 536

size (pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024

size() (pylablib.core.dataproc.image.ROI method), 148

size() (pylablib.core.utils.dictionary.Dictionary method), 378

size() (pylablib.core.utils.dictionary.DictionaryPointer method), 392

size() (pylablib.core.utils.dictionary.FilterTree method), 409

size() (pylablib.core.utils.dictionary.PrefixTree method), 401

skip() (pylablib.core.thread.callsync.QScheduledCall method), 333

skipped (pylablib.devices.Andor.AndorSDK3.TMissedFramesStatus attribute), 536

skipped (pylablib.devices.interface.camera.TFramesStatus attribute), 989

skipped() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 330

skipped() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331

SkippedCallError, 370

sleep() (pylablib.core.devio.SCP1.SCPIDevice method), 166

sleep() (pylablib.core.thread.controller.QTaskThread method), 360

sleep() (pylablib.core.thread.controller.QThreadController method), 344

sleep() (pylablib.devices.AWG.generic.GenericAWG method), 460

sleep() (pylablib.devices.AWG.specific.Agilent33220A method), 473

sleep() (pylablib.devices.AWG.specific.Agilent33500 method), 467

sleep() (pylablib.devices.AWG.specific.InstekAFG2000 method), 485

sleep() (pylablib.devices.AWG.specific.InstekAFG2225 method), 479

sleep() (pylablib.devices.AWG.specific.RigolDG1000 method), 503

sleep() (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 491

sleep() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 497

sleep() (pylablib.devices.Cryocon.base.Cryocon1x method), 602

sleep() (pylablib.devices.Cryomagnetics.base.LM500 method), 607

sleep() (pylablib.devices.Cryomagnetics.base.LM510 method), 611

sleep() (pylablib.devices.Keithley.multimeter.Keithley2110 method), 670

sleep() (pylablib.devices.Lakeshore.base.Lakeshore218 method), 676

sleep() (pylablib.devices.Lakeshore.base.Lakeshore370 method), 681

sleep() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 822

sleep() (pylablib.devices.Rigol.power\_supply.DP1116A method), 837

sleep() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 862

sleep() (pylablib.devices.Tektronix.base.DPO2000 method), 900

sleep() (pylablib.devices.Tektronix.base.ITektronixScope method), 887

sleep() (pylablib.devices.Tektronix.base.TDS2000 method), 894

sleep() (pylablib.devices.Thorlabs.misc.GenericPM method), 949

sleep() (pylablib.devices.Thorlabs.misc.PM160 method), 953

sleep() (pylablib.devices.Thorlabs.serial.FW method), 960

sleep() (pylablib.devices.Thorlabs.serial.FWv1 method), 963

sleep() (pylablib.devices.Thorlabs.serial.MDT69xA method), 966

sleep() (pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method), 956

sleep() (pylablib.devices.Voltcraft.multimeter.VC7055 method), 983

sliding\_average() (in module py-

[lablib.core.dataproc.filters](#)), 138  
[sliding\\_filter\(\)](#) (in module [pylablib.core.dataproc.filters](#)), 138  
[slope](#) ([pylablib.devices.Tektronix.base.TTriggerParameters](#) attribute), 881  
[SmarActError](#), 873  
[smov](#) ([pylablib.devices.Standa.base.TFullState](#) attribute), 877  
[snap\(\)](#) ([pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera](#) method), 521  
[snap\(\)](#) ([pylablib.devices.AlliedVision.Bonito.IBonitoCamera](#) method), 513  
[snap\(\)](#) ([pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera](#) method), 533  
[snap\(\)](#) ([pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera](#) method), 543  
[snap\(\)](#) ([pylablib.devices.Basler.pylon.BaslerPylonCamera](#) method), 584  
[snap\(\)](#) ([pylablib.devices.BitFlow.BitFlow.BitFlowCamera](#) method), 596  
[snap\(\)](#) ([pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber](#) method), 590  
[snap\(\)](#) ([pylablib.devices.DCAM.DCAM.DCAMCamera](#) method), 621  
[snap\(\)](#) ([pylablib.devices.IMAQ.IMAQ.IMAQCamera](#) method), 648  
[snap\(\)](#) ([pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber](#) method), 641  
[snap\(\)](#) ([pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera](#) method), 662  
[snap\(\)](#) ([pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera](#) method), 656  
[snap\(\)](#) ([pylablib.devices.interface.camera.IAttributeCamera](#) method), 1000  
[snap\(\)](#) ([pylablib.devices.interface.camera.IBinROICamera](#) method), 1019  
[snap\(\)](#) ([pylablib.devices.interface.camera.ICamera](#) method), 993  
[snap\(\)](#) ([pylablib.devices.interface.camera.IExposureCamera](#) method), 1009  
[snap\(\)](#) ([pylablib.devices.interface.camera.IGrabberAttributeCamera](#) method), 1005  
[snap\(\)](#) ([pylablib.devices.interface.camera.IROICamera](#) method), 1014  
[snap\(\)](#) ([pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera](#) method), 713  
[snap\(\)](#) ([pylablib.devices.PCO.SC2.PCOS2Camera](#) method), 762  
[snap\(\)](#) ([pylablib.devices.Photometrics.pvcam.PvcamCamera](#) method), 778  
[snap\(\)](#) ([pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera](#) method), 787  
[snap\(\)](#) ([pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera](#) method), 796  
[snap\(\)](#) ([pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera](#) method), 805  
[snap\(\)](#) ([pylablib.devices.PrincetonInstruments.picam.PicamCamera](#) method), 833  
[snap\(\)](#) ([pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera](#) method), 854  
[snap\(\)](#) ([pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber](#) method), 847  
[snap\(\)](#) ([pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera](#) method), 910  
[snap\(\)](#) ([pylablib.devices.uc480.uc480.UC480Camera](#) method), 1030  
[socket](#) ([pylablib.core.utils.net.ClientSocket](#) attribute), 441  
[SocketError](#), 440  
[SocketTimeout](#), 440  
[SocketTunnelService](#) (class in [pylablib.core.utils.rpyc\\_utils](#)), 446  
[software\\_version](#) ([pylablib.devices.Andor.AndorSDK3.TDeviceInfo](#) attribute), 536  
[software\\_version](#) ([pylablib.devices.LaserQuantum.base.TDeviceInfo](#) attribute), 682  
[software\\_version](#) ([pylablib.devices.SiliconSoftware.fgrab.TDeviceInfo](#) attribute), 841  
[Solstis](#) (class in [pylablib.devices.M2.solstis](#)), 701  
[sort\\_by\(\)](#) (in module [pylablib.core.dataproc.utils](#)), 163  
[sort\\_set\\_by\\_list\(\)](#) (in module [pylablib.core.utils.general](#)), 427  
[source](#) ([pylablib.devices.Lakeshore.base.TLakeshore218AnalogSettings](#) attribute), 672  
[source](#) ([pylablib.devices.Lakeshore.base.TLakeshore370AnalogSettings](#) attribute), 677  
[source](#) ([pylablib.devices.Tektronix.base.TTriggerParameters](#) attribute), 881  
[source](#) ([pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice.CommData](#) attribute), 917  
[source](#) ([pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice.CommShortData](#) attribute), 917  
[speed](#) ([pylablib.devices.Standa.base.TFullState](#) attribute), 877  
[speed](#) ([pylablib.devices.Standa.base.TMoveParams](#) attribute), 877  
[speed](#) ([pylablib.devices.Trinamic.base.TVelocityParams](#) attribute), 972  
[speed\\_freq](#) ([pylablib.devices.Photometrics.pvcam.TReadoutInfo](#) attribute), 772  
[speed\\_gain](#) ([pylablib.devices.Photometrics.pvcam.TReadoutInfo](#) attribute), 772  
[SpinBinFlowGroups](#) (in module [pylablib.core.utils.general](#)), 427

`split_into_bins()` (in module `pylablib.core.dataproc.filters`), 139  
`split_path()` (in module `pylablib.core.utils.dictionary`), 376  
`split_units()` (in module `pylablib.core.utils.units`), 454  
`SproutG` (class in `pylablib.devices.LighthousePhotonics.base`), 690  
`spwr` (`pylablib.devices.Standa.base.TFullState` attribute), 877  
`src` (`pylablib.core.thread.multicast_pool.TMulticast` attribute), 364  
`src` (`pylablib.devices.NKT.interbus.TInterbusTelegram` attribute), 725  
`sRGB_to_linear()` (in module `pylablib.devices.utils.color`), 1031  
`sstep` (`pylablib.devices.interface.camera.TAxisROILimit` attribute), 1010  
`Standa8SMC` (class in `pylablib.devices.Standa.base`), 878  
`StandaBackendError`, 876  
`StandaError`, 876  
`StandardIndicatorHandler` (class in `pylablib.core.gui.value_handling`), 325  
`StandardValueHandler` (class in `pylablib.core.gui.value_handling`), 315  
`start` (`pylablib.core.dataproc.utils.Range` property), 164  
`start` (`pylablib.core.gui.widgets.container.TTimerEvent` attribute), 235  
`start()` (in module `pylablib.core.thread.profile`), 366  
`start()` (`pylablib.core.devio.backend_logger.BackendLogger` method), 169  
`start()` (`pylablib.core.devio.comm_backend.RecordedDeviceBackend` method), 190  
`start()` (`pylablib.core.gui.widgets.container.IQContainer` method), 237  
`start()` (`pylablib.core.gui.widgets.container.IQWidgetContainer` method), 245  
`start()` (`pylablib.core.gui.widgets.container.QContainer` method), 240  
`start()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 259  
`start()` (`pylablib.core.gui.widgets.container.QFrameContainer` method), 254  
`start()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer` method), 263  
`start()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer` method), 271  
`start()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaContainerWidget` method), 268  
`start()` (`pylablib.core.gui.widgets.container.QTabContainer` method), 274  
`start()` (`pylablib.core.gui.widgets.container.QWidgetContainer` method), 250  
`start()` (`pylablib.core.gui.widgets.param_table.ParamTable` method), 295  
`start()` (`pylablib.core.gui.widgets.param_table.StatusTable` method), 305  
`start()` (`pylablib.core.thread.controller.QTaskThread` method), 361  
`start()` (`pylablib.core.thread.controller.QThreadController` method), 348  
`start()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.Call` method), 657  
`start()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.CallbackMan` method), 652  
`start()` (`pylablib.devices.NI.daq.NIDAQ` method), 720  
`start()` (`pylablib.devices.Windows.joystick.Joystick` method), 988  
`start_acquisition()` (`pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera` method), 521  
`start_acquisition()` (`pylablib.devices.AlliedVision.Bonito.IBonitoCamera` method), 513  
`start_acquisition()` (`pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera` method), 530  
`start_acquisition()` (`pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera` method), 539  
`start_acquisition()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera` method), 580  
`start_acquisition()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera` method), 596  
`start_acquisition()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber` method), 587  
`start_acquisition()` (`pylablib.devices.DCAM.DCAM.DCAMCamera` method), 617  
`start_acquisition()` (`pylablib.devices.IMAQ.IMAQ.IMAQCamera` method), 648  
`start_acquisition()` (`pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber` method), 637  
`start_acquisition()` (`pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera` method), 662  
`start_acquisition()` (`pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera` method), 652  
`start_acquisition()` (`pylablib.devices.interface.camera.IAttributeCamera` method), 1000

---

<code>start_acquisition()</code> ( <code>pylablib.devices.interface.camera.IBinROICamera</code> method), 1019	<code>start_bk()</code> ( <code>pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams</code> attribute), 920
<code>start_acquisition()</code> ( <code>pylablib.devices.interface.camera.ICamera</code> method), 990	<code>start_degas()</code> ( <code>pylablib.devices.Leybold.base.ITR90</code> method), 687
<code>start_acquisition()</code> ( <code>pylablib.devices.interface.camera.IExposureCamera</code> method), 1009	<code>start_fast_scan()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 704
<code>start_acquisition()</code> ( <code>pylablib.devices.interface.camera.IGrabberAttributeCamera</code> method), 1005	<code>start_fill()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 605
<code>start_acquisition()</code> ( <code>pylablib.devices.interface.camera.IROICamera</code> method), 1014	<code>start_fill()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 611
<code>start_acquisition()</code> ( <code>pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</code> method), 710	<code>start_fw()</code> ( <code>pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams</code> attribute), 920
<code>start_acquisition()</code> ( <code>pylablib.devices.PCO.SC2.PCOS2Camera</code> method), 757	<code>start_link()</code> ( <code>pylablib.devices.M2.base.ICEBlocDevice</code> method), 697
<code>start_acquisition()</code> ( <code>pylablib.devices.Photometrics.pvcam.PvcamCamera</code> method), 775	<code>start_link()</code> ( <code>pylablib.devices.M2.emm.EMM</code> method), 700
<code>start_acquisition()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> method), 787	<code>start_link()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 707
<code>start_acquisition()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 812	<code>start_loop()</code> ( <code>pylablib.core.devio.hid.HIDevice.Reader</code> method), 195
<code>start_acquisition()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 806	<code>start_loop()</code> ( <code>pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> method), 539
<code>start_acquisition()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 796	<code>start_loop()</code> ( <code>pylablib.devices.Basler.pylon.BaslerPylonCamera.Scheduler</code> method), 580
<code>start_acquisition()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera</code> method), 805	<code>start_loop()</code> ( <code>pylablib.devices.BitFlow.BitFlow.BitFlowCamera.BufferManager</code> method), 591
<code>start_acquisition()</code> ( <code>pylablib.devices.PrincetonInstruments.picam.PicamCamera</code> method), 829	<code>start_loop()</code> ( <code>pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.BufferManager</code> method), 587
<code>start_acquisition()</code> ( <code>pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> method), 854	<code>start_loop()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 806
<code>start_acquisition()</code> ( <code>pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> method), 844	<code>start_loop()</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera</code> method), 798
<code>start_acquisition()</code> ( <code>pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera</code> method), 906	<code>start_loop()</code> ( <code>pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> method), 848
<code>start_acquisition()</code> ( <code>pylablib.devices.uc480.uc480.UC480Camera</code> method), 1026	<code>start_loop()</code> ( <code>pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber</code> method), 843
<code>start_batch_job()</code> ( <code>pylablib.core.thread.controller.QTaskThread</code> method), 353	<code>start_measurement()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 605
	<code>start_measurement()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 611
	<code>start_measurement()</code> ( <code>pylablib.devices.HighFinesse.wlm.WLM</code> method), 626
	<code>start_pulse_output()</code> ( <code>pylablib.devices.NI.daq.NIDAQ</code> method), 724
	<code>start_terascan()</code> ( <code>pylablib.devices.M2.emm.EMM</code> method), 698
	<code>start_terascan()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 704
	<code>start_timer()</code> ( <code>pylablib.core.gui.widgets.container.IQContainer</code> method), 236



[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.IQWidgetContainer attribute), 245  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QContainer attribute), 240  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QDialogContainer attribute), 259  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QFrameContainer attribute), 254  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QGroupBoxContainer attribute), 264  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer attribute), 271  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainedWidget attribute), 268  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QTabContainer attribute), 274  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.container.QWidgetContainer attribute), 250  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.param\_table.ParamTable attribute), 295  
[start\\_timer\(\)](#) (pylablib.core.gui.widgets.param\_table.StatusTable attribute), 306  
[started](#) (pylablib.core.thread.controller.QTaskThread attribute), 361  
[started](#) (pylablib.core.thread.controller.QThreadController attribute), 342  
[state](#) (pylablib.devices.Windows.joystick.TJoystickEventEx attribute), 987  
[status](#) (pylablib.devices.Leybold.base.TUpdateValue attribute), 685  
[status](#) (pylablib.devices.PCO.SC2.TCameraStatus attribute), 755  
[status](#) (pylablib.devices.Trinamic.base.TTMCM1110ReplyData attribute), 972  
[status](#) (pylablib.devices.uc480.uc480.TCameraInfo attribute), 1023  
[status\\_bits](#) (pylablib.devices.Attocube.anc350.ANC350 attribute), 571  
[status\\_bits](#) (pylablib.devices.Thorlabs.kinesis.KinesisDevice attribute), 921  
[status\\_bits](#) (pylablib.devices.Thorlabs.kinesis.KinesisMotor attribute), 934  
[status\\_bits](#) (pylablib.devices.Thorlabs.kinesis.KinesisPiezoController attribute), 941  
[status\\_bits](#) (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor attribute), 938  
[status\\_bits](#) (pylablib.devices.Thorlabs.kinesis.MFF attribute), 927  
[StatusLineChecker](#) (class in pylablib.devices.interface.camera), 1019  
[StatusLineChecker](#) (class in pylablib.devices.PCO.SC2), 763  
[StatusLineChecker](#) (class in pylablib.devices.PhotonFocus.PhotonFocus), 813  
[StatusTable](#) (class in pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614  
[step](#) (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614  
[step\\_bk](#) (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920  
[step\\_fw](#) (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920  
[step\\_size](#) (pylablib.devices.Thorlabs.kinesis.TJogParams attribute), 919  
[step\\_size\\_bk](#) (pylablib.devices.Thorlabs.kinesis.TPZMotorJogParams attribute), 921  
[step\\_size\\_fw](#) (pylablib.devices.Thorlabs.kinesis.TPZMotorJogParams attribute), 921  
[step\\_voltage\(\)](#) (pylablib.devices.OZOptics.base.EPC04 method), 745  
[steps\\_per\\_rev](#) (pylablib.devices.Standa.base.TStepperMotorCalibration attribute), 877  
[stitched\\_scan\(\)](#) (pylablib.devices.Sirah.tuner.MatisseTuner method), 867  
[stitched\\_scan\\_gen\(\)](#) (pylablib.devices.Sirah.tuner.MatisseTuner method), 867  
[stop](#) (pylablib.core.dataproc.utils.Range property), 164  
[stop](#) (pylablib.core.gui.widgets.container.TTimerEvent attribute), 235  
[stop\(\)](#) (in module pylablib.core.thread.profile), 366  
[stop\(\)](#) (pylablib.core.devio.backend\_logger.BackendLogger method), 169  
[stop\(\)](#) (pylablib.core.devio.comm\_backend.RecordedDeviceBackend method), 190  
[stop\(\)](#) (pylablib.core.gui.widgets.container.IQContainer method), 237  
[stop\(\)](#) (pylablib.core.gui.widgets.container.IQWidgetContainer method), 245  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QContainer method), 240  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QDialogContainer method), 259  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QFrameContainer method), 254  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 264  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 271  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainedWidget method), 268  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QTabContainer method), 274  
[stop\(\)](#) (pylablib.core.gui.widgets.container.QWidgetContainer method), 250  
[stop\(\)](#) (pylablib.core.gui.widgets.param\_table.ParamTable attribute), 295

method), 295

stop() (pylablib.core.gui.widgets.param\_table.StatusTable method), 306

stop() (pylablib.core.thread.controller.QTaskThread method), 361

stop() (pylablib.core.thread.controller.QThreadController method), 348

stop() (pylablib.core.utils.general.Countdown method), 430

stop() (pylablib.devices.Arcus.performax.Performax2EXStage method), 560

stop() (pylablib.devices.Arcus.performax.Performax4EXStage method), 554

stop() (pylablib.devices.Arcus.performax.PerformaxDMXJSASage method), 561

stop() (pylablib.devices.Attocube.anc300.ANC300 method), 568

stop() (pylablib.devices.Attocube.anc350.ANC350 method), 572

stop() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.CallbackManager method), 657

stop() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera.CallbackManager method), 652

stop() (pylablib.devices.Newport.picomotor.Picomotor8742 method), 738

stop() (pylablib.devices.NI.daq.NIDAQ method), 720

stop() (pylablib.devices.PhysikInstrumente.base.PIE516 method), 817

stop() (pylablib.devices.SmarAct.MCS2.MCS2 method), 871

stop() (pylablib.devices.SmarAct.scu3d.SC3d method), 875

stop() (pylablib.devices.Standa.base.Standa8SMC method), 879

stop() (pylablib.devices.Thorlabs.kinesis.KinesisMotor method), 930

stop() (pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 935

stop() (pylablib.devices.Trinamic.base.TMCM1110 method), 973

stop() (pylablib.devices.Trinamic.base.TMCMx110 method), 980

stop() (pylablib.devices.Windows.joystick.Joystick method), 988

stop\_acquisition() (pylablib.devices.AlliedVision.Bonito.BonitoIMAQCamera method), 521

stop\_acquisition() (pylablib.devices.AlliedVision.Bonito.IBonitoCamera method), 513

stop\_acquisition() (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera method), 530

stop\_acquisition() (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera method), 539

stop\_acquisition() (pylablib.devices.Basler.pylon.BaslerPylonCamera method), 580

stop\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowCamera method), 596

stop\_acquisition() (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber method), 587

stop\_acquisition() (pylablib.devices.DCAM.DCAM.DCAMCamera method), 617

stop\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQCamera method), 648

stop\_acquisition() (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber method), 648

stop\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera.CallbackManager method), 662

stop\_acquisition() (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera method), 653

stop\_acquisition() (pylablib.devices.interface.camera.IAttributeCamera method), 1000

stop\_acquisition() (pylablib.devices.interface.camera.IBinROICamera method), 1019

stop\_acquisition() (pylablib.devices.interface.camera.ICamera method), 990

stop\_acquisition() (pylablib.devices.interface.camera.IExposureCamera method), 1010

stop\_acquisition() (pylablib.devices.interface.camera.IGrabberAttributeCamera method), 1005

stop\_acquisition() (pylablib.devices.interface.camera.IROICamera method), 1014

stop\_acquisition() (pylablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera method), 710

stop\_acquisition() (pylablib.devices.PCO.SC2.PCOSC2Camera method), 758

stop\_acquisition() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 775

stop\_acquisition() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 775

stop\_acquisition() (pylablib.devices.Photometrics.pvcam.PvcamCamera method), 775

`lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` method), 901  
`method`), 787 `stop_grabbing()` (py-  
`stop_acquisition()` (py- `lablib.devices.Tektronix.base.ITektronixScope`  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera` method), 882  
`method`), 812 `stop_grabbing()` (py-  
`stop_acquisition()` (py- `lablib.devices.Tektronix.base.TDS2000`  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACamera` method), 894  
`method`), 796 `stop_loop()` (`pylablib.core.devio.hid.HIDevice.Reader`  
`stop_acquisition()` (py- `method`), 195  
`lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiS3000` (py-  
`method`), 805 `method`), 539  
`stop_acquisition()` (py- `stop_loop()` (`pylablib.devices.Basler.pylon.BaslerPylonCamera.Schedule`  
`lablib.devices.PrincetonInstruments.picam.PicamCamera` method), 580  
`method`), 830 `stop_loop()` (`pylablib.devices.BitFlow.BitFlow.BitFlowCamera.BufferMa`  
`stop_acquisition()` (py- `method`), 591  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` (py-  
`method`), 854 `stop_loop()` (`pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber.Bu`  
`method`), 587  
`stop_acquisition()` (py- `stop_loop()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBit`  
`lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber` method), 806  
`method`), 844 `stop_loop()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiS`  
`stop_acquisition()` (py- `method`), 798  
`lablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera` `stop_loop()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCam`  
`method`), 906 `method`), 848  
`stop_acquisition()` (py- `stop_loop()` (`pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrame`  
`lablib.devices.uc480.uc480.UC480Camera` `method`), 843  
`method`), 1026 `stop_lower` (`pylablib.devices.Sirah.Matisse.TScanMode`  
`stop_all_controllers()` (in module `py-` `attribute`), 856  
`lablib.core.thread.controller`), 364 `stop_measurement()` (py-  
`stop_all_operation()` (py- `lablib.devices.HighFinesse.wlm.WLM` method),  
`lablib.devices.M2.emm.EMM` method), 699 626  
`stop_all_operation()` (py- `stop_mode` (`pylablib.devices.Thorlabs.kinesis.TJogParams`  
`lablib.devices.M2.solstis.Solstis` method), `attribute`), 919  
705 `stop_pulse_output()` (py-  
`stop_app()` (in module `pylablib.core.thread.controller`), `lablib.devices.NI.daq.NIDAQ` method), 724  
364 `stop_scan_web()` (`pylablib.devices.M2.solstis.Solstis`  
`stop_batch_job()` (py- `method`), 705  
`lablib.core.thread.controller.QTaskThread` `stop_terascan()` (`pylablib.devices.M2.emm.EMM`  
`method`), 353 `method`), 699  
`stop_coarse_tuning()` (py- `stop_terascan()` (`pylablib.devices.M2.solstis.Solstis`  
`lablib.devices.M2.solstis.Solstis` method), `method`), 704  
702 `stop_timer()` (`pylablib.core.gui.widgets.container.IQContainer`  
`stop_controller()` (in module `py-` `method`), 236  
`lablib.core.thread.controller`), 364 `stop_timer()` (`pylablib.core.gui.widgets.container.IQWidgetContainer`  
`stop_degas()` (`pylablib.devices.Leybold.base.ITR90` `method`), 245  
`method`), 687 `stop_timer()` (`pylablib.core.gui.widgets.container.QContainer`  
`stop_fast_scan()` (`pylablib.devices.M2.solstis.Solstis` `method`), 240  
`method`), 705 `stop_timer()` (`pylablib.core.gui.widgets.container.QDialogContainer`  
`stop_fine_tuning()` (`pylablib.devices.M2.emm.EMM` `method`), 259  
`method`), 698 `stop_timer()` (`pylablib.core.gui.widgets.container.QFrameContainer`  
`stop_fine_tuning()` (py- `method`), 254  
`lablib.devices.M2.solstis.Solstis` method), `stop_timer()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer`  
702 `method`), 264  
`stop_grabbing()` (py- `stop_timer()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer`  
`lablib.devices.Tektronix.base.DPO2000` `method`), 271

[stop\\_timer\(\) \(pylablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaWidget\), 433](#)  
[stop\\_timer\(\) \(pylablib.core.gui.widgets.container.QTabContainer.QTabWidget\), 433](#)  
[stop\\_timer\(\) \(pylablib.core.gui.widgets.container.QWidget.QWidget\), 433](#)  
[stop\\_timer\(\) \(pylablib.core.gui.widgets.param\\_table.ParamTable\), 295](#)  
[stop\\_timer\(\) \(pylablib.core.gui.widgets.param\\_table.StatTable\), 306](#)  
[stop\\_upper \(pylablib.devices.Sirah.Matisse.TScanMode attribute\), 856](#)  
[store\\_axis\\_parameter\(\) \(pylablib.devices.Trinamic.base.TMCM1110 method\), 972](#)  
[store\\_axis\\_parameter\(\) \(pylablib.devices.Trinamic.base.TMCMx110 method\), 980](#)  
[store\\_defaults\(\) \(pylablib.devices.Arcus.performax.GenericPerformax method\), 552](#)  
[store\\_defaults\(\) \(pylablib.devices.Arcus.performax.Performax2EXStage method\), 560](#)  
[store\\_defaults\(\) \(pylablib.devices.Arcus.performax.Performax4EXStage method\), 556](#)  
[store\\_defaults\(\) \(pylablib.devices.Arcus.performax.PerformaxDMXJSStage method\), 563](#)  
[store\\_parameters\(\) \(pylablib.devices.Thorlabs.elliptec.ElliptecMotor method\), 913](#)  
[store\\_settings\(\) \(pylablib.devices.Thorlabs.serial.FW method\), 958](#)  
[str\\_to\\_float\(\) \(in module py-lablib.core.gui.formatter\), 307](#)  
[strconv\(\) \(in module pylablib.core.utils.ctypes\\_wrap\), 374](#)  
[StrDumper \(class in pylablib.core.utils.strdump\), 448](#)  
[StreamFileLogger \(class in py-lablib.core.utils.general\), 431](#)  
[strerror \(pylablib.core.thread.threadprop.TimeoutThreadError attribute\), 369](#)  
[strerror \(pylablib.core.utils.net.SocketError attribute\), 440](#)  
[strerror \(pylablib.core.utils.net.SocketTimeout attribute\), 440](#)  
[stride \(pylablib.devices.Andor.AndorSDK3.TFrameInfo attribute\), 536](#)  
[string\\_equal\(\) \(in module pylablib.core.utils.string\), 449](#)  
[string\\_list\\_idx\(\) \(in module py-lablib.core.utils.string\), 449](#)  
[StringFilter \(class in pylablib.core.utils.string\), 450](#)  
[subscribe\(\) \(in module pylablib.core.utils.ctypes\\_wrap\), 374](#)  
[subscribe\\_column\(\) \(pylablib.core.dataproc.table\\_wrap.Array1DWrapper method\), 154](#)  
[subscribe\\_column\(\) \(pylablib.core.dataproc.table\\_wrap.I1DWrapper method\), 153](#)  
[subscribe\\_column\(\) \(pylablib.core.dataproc.table\\_wrap.Series1DWrapper method\), 155](#)  
[subscribe\\_commsync\(\) \(py-lablib.core.thread.controller.QTaskThread method\), 354](#)  
[subscribe\\_direct\(\) \(py-lablib.core.thread.controller.QTaskThread method\), 361](#)  
[subscribe\\_direct\(\) \(py-lablib.core.thread.controller.QThreadController method\), 345](#)  
[subscribe\\_direct\(\) \(py-lablib.core.thread.multicast\\_pool.MulticastPool method\), 364](#)  
[subscribe\\_sync\(\) \(py-lablib.core.thread.controller.QTaskThread method\), 362](#)  
[subscribe\\_sync\(\) \(py-lablib.core.thread.controller.QThreadController method\), 344](#)  
[subtable\(\) \(pylablib.core.dataproc.table\\_wrap.Array2DWrapper method\), 158](#)  
[subtable\(\) \(pylablib.core.dataproc.table\\_wrap.DataFrame2DWrapper method\), 160](#)  
[subtable\(\) \(pylablib.core.dataproc.table\\_wrap.I2DWrapper method\), 156](#)  
[subtract\\_baseline\(\) \(in module py-lablib.core.dataproc.feature\), 135](#)  
[subtype \(pylablib.devices.Thorlabs.misc.TPMSensorInfo attribute\), 945](#)  
[success\\_wait\(\) \(pylablib.core.thread.callsync.QCallResultSynchronizer method\), 331](#)  
[success\\_wait\(\) \(pylablib.core.thread.callsync.QDirectResultSynchronizer method\), 332](#)  
[success\\_wait\(\) \(pylablib.core.thread.notifier.ISkippableNotifier method\), 366](#)  
[success\\_wait\(\) \(pylablib.core.thread.synchronizing.QThreadNotifier method\), 367](#)  
[sum \(pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings attribute\), 942](#)  
[summary\(\) \(pylablib.core.utils.general.TimeTracker method\), 431](#)  
[SuperKExtremeInterbusModule \(class in py-lablib.devices.NKT.interbus\), 729](#)  
[SuperKFrontPanelInterbusModule \(class in py-lablib.devices.NKT.interbus\), 730](#)



SuperKSelectDriverInterbusModule (class in py-  
     lablib.devices.NKT.interbus), 731  
 SuperKSelectInterbusModule (class in py-  
     lablib.devices.NKT.interbus), 732  
 svec (pylablib.core.dataproc.ctransform\_fallback.CLinear2DTransform  
     property), 134  
 sw\_kind (pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams  
     attribute), 920  
 sw\_position\_ccw (py-  
     lablib.devices.Thorlabs.kinesis.TLimitSwitchParams  
     attribute), 920  
 sw\_position\_cw (pylablib.devices.Thorlabs.kinesis.TLimitSwitchParams  
     attribute), 920  
 sw\_ver (pylablib.devices.ElektroAutomatik.base.TDeviceInfo  
     attribute), 622  
 switch\_speed (pylablib.devices.Trinamic.base.THomeParam  
     attribute), 972  
 swnd (pylablib.devices.Standa.base.TFullState attribute),  
     877  
 swver (pylablib.devices.KJL.base.TKJL300DeviceInfo  
     attribute), 663  
 swver (pylablib.devices.Leybold.base.TDeviceInfo  
     attribute), 685  
 sync\_controller() (in module py-  
     lablib.core.thread.controller), 363  
 sync\_exec\_point() (py-  
     lablib.core.thread.controller.QTaskThread  
     method), 362  
 sync\_exec\_point() (py-  
     lablib.core.thread.controller.QThreadController  
     method), 349  
 sync\_phase() (pylablib.devices.AWG.generic.GenericAWG  
     method), 457  
 sync\_phase() (pylablib.devices.AWG.specific.Agilent33220A  
     method), 473  
 sync\_phase() (pylablib.devices.AWG.specific.Agilent33500A  
     method), 467  
 sync\_phase() (pylablib.devices.AWG.specific.InstekAFG2000  
     method), 485  
 sync\_phase() (pylablib.devices.AWG.specific.InstekAFG2225  
     method), 479  
 sync\_phase() (pylablib.devices.AWG.specific.RigolDG1000  
     method), 498  
 sync\_phase() (pylablib.devices.AWG.specific.RSInstekAFG21000  
     method), 491  
 sync\_phase() (pylablib.devices.AWG.specific.TektronixAFG1000  
     method), 497  
 sync\_stop() (pylablib.core.thread.controller.QTaskThread  
     method), 362  
 sync\_stop() (pylablib.core.thread.controller.QThreadController  
     method), 348  
 sync\_variable() (py-  
     lablib.core.thread.controller.QTaskThread  
     method), 363  
 sync\_variable() (py-  
     lablib.core.thread.controller.QThreadController  
     method), 348  
 sync\_with\_ai (pylablib.devices.NI.daq.TVoltageOutputClockParameters  
     attribute), 718  
 system (pylablib.devices.Photometrics.pvcam.TDeviceInfo  
     attribute), 771  
 system\_info (pylablib.devices.SiliconSoftware.fgrab.TDeviceInfo  
     attribute), 841  
 table\_entry\_builder() (in module py-  
     lablib.core.fileio.dict\_entry), 208  
 TableBinaryOutputFileFormat (class in py-  
     lablib.core.fileio.savefile), 227  
 TableStreamFile (class in py-  
     lablib.core.fileio.table\_stream), 231  
 TAcqProgress (class in py-  
     lablib.devices.Andor.AndorSDK2), 523  
 TAcqTimings (class in py-  
     lablib.devices.interface.camera), 1005  
 TAcquiredFramesStatus (class in py-  
     lablib.devices.uc480.uc480), 1023  
 tag (pylablib.core.thread.multicast\_pool.TMulticast at-  
     tribute), 364  
 tags (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo  
     attribute), 839  
 TAppletInfo (class in py-  
     lablib.devices.SiliconSoftware.fgrab), 838  
 TAveragingParameters (class in py-  
     lablib.devices.Keithley.multimeter), 666  
 TAxisROIILimit (class in py-  
     lablib.devices.interface.camera), 1010  
 TBoardInfo (class in py-  
     lablib.devices.SiliconSoftware.fgrab), 838  
 TCameraInfo (class in pylablib.devices.Basler.pylon),  
     575  
 TCameraInfo (class in py-  
     lablib.devices.IMAQdx.IMAQdx), 648  
 TCameraInfo (class in py-  
     lablib.devices.Mightex.MightexSSeries),  
     707  
 TCameraInfo (class in py-  
     lablib.devices.PhotonFocus.PhotonFocus),  
     780  
 TCameraInfo (class in py-  
     lablib.devices.PrincetonInstruments.picam),  
     824  
 TCameraInfo (class in pylablib.devices.uc480.uc480),  
     1022  
 TCameraStatus (class in pylablib.devices.PCO.SC2),  
     754  
 TChild (class in pylablib.core.gui.widgets.container),  
     235

TCLMoveParams	(class in py-lablib.devices.SmarAct.MCS2), 869	py-lablib.devices.Newport.picomotor), 736
TColorFormat	(class in py-lablib.devices.Thorlabs.TLCamera), 903	TDeviceInfo (class in pylablib.devices.NI.daq), 717
TColorInfo	(class in py-lablib.devices.Thorlabs.TLCamera), 903	TDeviceInfo (class in pylablib.devices.Ophir.base), 751
TConfigurationParameters	(class in py-lablib.devices.Keithley.multimeter), 666	TDeviceInfo (class in pylablib.devices.PCO.SC2), 754
TConversionClass	(class in pylablib.core.utils.string), 451	TDeviceInfo (class in py-lablib.devices.Photometrics.pvcam), 771
TCycleTimings	(class in py-lablib.devices.Andor.AndorSDK2), 523	TDeviceInfo (class in py-lablib.devices.PhotonFocus.PhotonFocus), 781
TDefaultCallInfo	(class in py-lablib.core.thread.callsync), 333	TDeviceInfo (class in py-lablib.devices.PrincetonInstruments.picam), 827
TDeviceDescription	(class in pylablib.core.devio.hid), 194	TDeviceInfo (class in py-lablib.devices.SiliconSoftware.fgrab), 840
TDeviceInfo	(class in py-lablib.devices.AlliedVision.Bonito), 507	TDeviceInfo (class in pylablib.devices.SmarAct.MCS2), 868
TDeviceInfo	(class in py-lablib.devices.Andor.AndorSDK2), 523	TDeviceInfo (class in pylablib.devices.SmarAct.scu3d), 874
TDeviceInfo	(class in py-lablib.devices.Andor.AndorSDK3), 536	TDeviceInfo (class in py-lablib.devices.Thorlabs.elliptec), 911
TDeviceInfo	(class in py-lablib.devices.Andor.Shamrock), 544	TDeviceInfo (class in py-lablib.devices.Thorlabs.kinesis), 916
TDeviceInfo	(class in py-lablib.devices.Attocube.anc300), 566	TDeviceInfo (class in py-lablib.devices.Thorlabs.TLCamera), 902
TDeviceInfo	(class in pylablib.devices.Basler.pylon), 577	TDeviceInfo (class in pylablib.devices.Toptica.ibeam), 968
TDeviceInfo	(class in py-lablib.devices.BitFlow.BitFlow), 585	TDeviceInfo (class in pylablib.devices.uc480.uc480), 1023
TDeviceInfo	(class in pylablib.devices.DCAM.DCAM), 615	TDeviceInfo (class in py-lablib.devices.Windows.joystick), 987
TDeviceInfo	(class in py-lablib.devices.ElektroAutomatik.base), 622	TDS2000 (class in pylablib.devices.Tektronix.base), 888
TDeviceInfo	(class in py-lablib.devices.HighFinesse.wlm), 625	TektronixAFG1000 (class in py-lablib.devices.AWG.specific), 492
TDeviceInfo	(class in pylablib.devices.Hubner.Cobolt), 629	TektronixBackendError, 880
TDeviceInfo	(class in pylablib.devices.IMAQ.IMAQ), 633	TektronixError, 880
TDeviceInfo	(class in py-lablib.devices.IMAQdx.IMAQdx), 650	temp (pylablib.devices.Standa.base.TFullState attribute), 877
TDeviceInfo	(class in py-lablib.devices.LaserQuantum.base), 682	temp_library_parameters() (in module py-lablib.core.utils.library_parameters), 437
TDeviceInfo	(class in pylablib.devices.Leybold.base), 685	temp_open() (pylablib.devices.Andor.AndorSDK2.LibraryController method), 522
TDeviceInfo	(class in py-lablib.devices.LighthousePhotonics.base), 689	temp_open() (pylablib.devices.Andor.AndorSDK3.LibraryController method), 534
TDeviceInfo	(class in pylablib.devices.Lumel.base), 692	temp_open() (pylablib.devices.Andor.Shamrock.LibraryController method), 544
TDeviceInfo	(class in py-lablib.devices.Mightex.MightexSSeries), 708	temp_open() (pylablib.devices.Basler.pylon.LibraryController method), 575
TDeviceInfo	(class in py-lablib.devices.Mightex.MightexSSeries), 708	temp_open() (pylablib.devices.DCAM.DCAM.LibraryController method), 613
TDeviceInfo	(class in py-lablib.devices.Mightex.MightexSSeries), 708	temp_open() (pylablib.devices.Mightex.MightexSSeries.LibraryController method), 708
TDeviceInfo	(class in py-lablib.devices.Mightex.MightexSSeries), 708	temp_open() (pylablib.devices.Photometrics.pvcam.LibraryController method), 708

- method), 769
- temp\_open() (pylablib.devices.PhotonFocus.PhotonFocus.TFullApertureInfo (class in py-lablib.devices.SiliconSoftware.fgrab), 839
- temp\_open() (pylablib.devices.PrincetonInstruments.picam.TFullBoardInfo (in module py-lablib.devices.SiliconSoftware.fgrab), 838
- temp\_open() (pylablib.devices.SmarAct.MCS2.LibraryController.TFullState (class in pylablib.devices.Standa.base), 877
- temp\_open() (pylablib.devices.SmarAct.scu3d.LibraryController.TGenericFunctionParameters (class in py-lablib.devices.Keithley.multimeter), 666
- temp\_open() (pylablib.devices.Thorlabs.TLCamera.LibraryController.TGenMoveParams (class in py-lablib.devices.Thorlabs.kinesis), 919
- temp\_open() (pylablib.devices.thorlabs.TLCamera.LibraryController.TGratingInfo (class in py-lablib.devices.Andor.Shamrock), 545
- temp\_open() (pylablib.devices.utils.load\_lib.LibraryController.THeadInfo (class in pylablib.devices.Ophir.base), 750
- TempFile (class in pylablib.core.utils.files), 413
- TEngineType (class in pylablib.devices.Standa.base), 876
- test\_columns\_line() (in module py-lablib.core.fileio.loadfile\_utils), 216
- test\_row\_type() (in module py-lablib.core.fileio.loadfile\_utils), 216
- test\_savetime\_comment() (in module py-lablib.core.fileio.loadfile\_utils), 216
- TextEdit (class in pylablib.core.gui.widgets.edit), 274
- TextLabel (class in pylablib.core.gui.widgets.label), 277
- TF100 (class in pylablib.devices.OZOptics.base), 741
- TFastpiezoCtlParameters (class in py-lablib.devices.Sirah.Matisse), 855
- TFlipperParameters (class in py-lablib.devices.Thorlabs.kinesis), 923
- TFrameInfo (class in py-lablib.devices.Andor.AndorSDK3), 536
- TFrameInfo (class in pylablib.devices.DCAM.DCAM), 615
- TFrameInfo (class in pylablib.devices.interface.camera), 989
- TFrameInfo (class in pylablib.devices.PCO.SC2), 755
- TFrameInfo (class in py-lablib.devices.Photometrics.pvcam), 771
- TFrameInfo (class in py-lablib.devices.PrincetonInstruments.picam), 827
- TFrameInfo (class in py-lablib.devices.SiliconSoftware.fgrab), 841
- TFrameInfo (class in py-lablib.devices.Thorlabs.TLCamera), 903
- TFrameInfo (class in pylablib.devices.uc480.uc480), 1024
- TFramePosition (class in py-lablib.devices.interface.camera), 989
- TFrameSize (class in pylablib.devices.interface.camera), 989
- TFramesStatus (class in py-lablib.devices.interface.camera), 989
- TFrequencyFunctionParameters (class in py-lablib.devices.Keithley.multimeter), 666
- TFullApertureInfo (class in py-lablib.devices.SiliconSoftware.fgrab), 839
- TFullBoardInfo (in module py-lablib.devices.SiliconSoftware.fgrab), 838
- TFullState (class in pylablib.devices.Standa.base), 877
- TGenericFunctionParameters (class in py-lablib.devices.Keithley.multimeter), 666
- TGenMoveParams (class in py-lablib.devices.Thorlabs.kinesis), 919
- TGratingInfo (class in py-lablib.devices.Andor.Shamrock), 545
- THeadInfo (class in pylablib.devices.Ophir.base), 750
- thinet\_clear\_errors() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_get\_position() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_get\_range() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_get\_status() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_get\_status\_n() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_home() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_is\_moving() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_move\_to() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_stop() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 858
- thinet\_wait\_move() (py-lablib.devices.Sirah.Matisse.SirahMatisse method), 858
- THomeParams (class in py-lablib.devices.Thorlabs.kinesis), 919
- THomeParams (class in pylablib.devices.Trinamic.base), 972
- ThorlabsBackendError, 911
- ThorlabsError, 911
- ThorlabsSerialInterface (class in py-lablib.devices.Thorlabs.serial), 954
- ThorlabsTimeoutError, 911
- ThorlabsTLCamera (class in py-lablib.devices.Thorlabs.TLCamera), 903
- ThorlabsTLCamera.RingBuffer (class in py-lablib.devices.Thorlabs.TLCamera), 904

[ThreadError](#), 368  
[time\\_left\(\)](#) (pylablib.core.thread.controller.QTaskThreadTimer attribute), 352  
[time\\_left\(\)](#) (pylablib.core.utils.general.CountdownTimer attribute), 430  
[time\\_left\(\)](#) (pylablib.core.utils.general.Timer attribute), 430  
[time\\_passed\(\)](#) (pylablib.core.utils.general.CountdownTimer attribute), 430  
[TimeoutError](#) (pylablib.devices.AlliedVision.Bonito.BonitoCamera attribute), 513  
[TimeoutError](#) (pylablib.devices.AlliedVision.Bonito.IBonitoCamera attribute), 509  
[TimeoutError](#) (pylablib.devices.Andor.AndorSDK2.AndorSDK2Camera attribute), 524  
[TimeoutError](#) (pylablib.devices.Andor.AndorSDK3.AndorSDK3Camera attribute), 537  
[TimeoutError](#) (pylablib.devices.Basler.pylon.BaslerPylonCamera attribute), 578  
[TimeoutError](#) (pylablib.devices.BitFlow.BitFlow.BitFlowCamera attribute), 591  
[TimeoutError](#) (pylablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber attribute), 585  
[TimeoutError](#) (pylablib.devices.DCAM.DCAM.DCAMCamera attribute), 615  
[TimeoutError](#) (pylablib.devices.IMAQ.IMAQ.IMAQCamera attribute), 641  
[TimeoutError](#) (pylablib.devices.IMAQ.IMAQ.IMAQFrameGrabber attribute), 634  
[TimeoutError](#) (pylablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera attribute), 657  
[TimeoutError](#) (pylablib.devices.IMAQdx.IMAQdx.IMAQdxCamera attribute), 651  
[TimeoutError](#) (pylablib.devices.interface.camera.IAttributeCamera attribute), 996  
[TimeoutError](#) (pylablib.devices.interface.camera.IBinROICamera attribute), 1015  
[TimeoutError](#) (pylablib.devices.interface.camera.ICamera attribute), 990  
[TimeoutError](#) (pylablib.devices.interface.camera.IExposureCamera attribute), 1006  
[TimeoutError](#) (pylablib.devices.interface.camera.IGrabberAttributeCamera attribute), 1001  
[TimeoutError](#) (pylablib.devices.interface.camera.IROICamera attribute), 1011  
[TimeoutError](#) (pylablib.devices.Mightex.MightexSSeries.MightexSSSeriesCamera attribute), 708  
[TimeoutError](#) (pylablib.devices.PCO.SC2.PCOSC2Camera attribute), 755  
[TimeoutError](#) (pylablib.devices.Photometrics.pvcam.PvcamCamera attribute), 772  
[TimeoutError](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera attribute), 784  
[TimeoutError](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera attribute), 806  
[TimeoutError](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera attribute), 788  
[TimeoutError](#) (pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusCamera attribute), 798  
[TimeoutError](#) (pylablib.devices.PrincetonInstruments.picam.PicamCamera attribute), 828  
[TimeoutError](#) (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera attribute), 848  
[TimeoutError](#) (pylablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabber attribute), 841  
[TimeoutError](#) (pylablib.devices.Thorlabs.TLCamera.ThorlabsTLCamera attribute), 903  
[TimeoutError](#) (pylablib.devices.uc480.uc480.UC480Camera attribute), 1025  
[Timer](#) (class in pylablib.core.utils.general), 430  
[Timer](#) (pylablib.core.gui.widgets.container.TTimer attribute), 235  
[Timer](#) (pylablib.core.gui.widgets.container.TTimerEvent attribute), 235  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.IQContainer attribute), 236  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.IQWidgetContainer attribute), 242  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QContainer attribute), 238  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QDialogContainer attribute), 255  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QFrameContainer attribute), 250  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QGroupBoxContainer attribute), 260  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer attribute), 269  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QScrollAreaContainer.QContainer attribute), 264  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QTabContainer attribute), 272  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.container.QWidgetContainer attribute), 246  
[TimerUIDGenerator](#) (pylablib.core.gui.widgets.param\_table.ParamTable attribute), 390



TimerUIDGenerator	(py-lablib.core.gui.widgets.param_table.StatusTable attribute), 296	TLakeshore218FilterSettings (class in py-lablib.devices.Lakeshore.base), 672	
timestamp	(pylablib.devices.SiliconSoftware.fgrab.TFrameInfo attribute), 841	TLakeshore370AnalogSettings (class in py-lablib.devices.Lakeshore.base), 677	
timestamp	(pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024	TLakeshore370FilterSettings (class in py-lablib.devices.Lakeshore.base), 677	
timestamp	(pylablib.devices.Windows.joystick.TJoystickEvent attribute), 987	TLakeshore370RangeSettings (class in py-lablib.devices.Lakeshore.base), 677	
timestamp	(pylablib.devices.Windows.joystick.TJoystickEventEx attribute), 987	TLibraryCloseResult (class in py-lablib.devices.utils.load_lib), 1033	
timestamp_dev	(pylablib.devices.Andor.AndorSDK3.TFrameInfo attribute), 536	TLibraryOpenResult (class in py-lablib.devices.utils.load_lib), 1033	
timestamp_dev	(pylablib.devices.uc480.uc480.TFrameInfo attribute), 1024	TLimitSwitchParams (class in py-lablib.devices.Thorlabs.kinesis), 920	
timestamp_end	(pylablib.devices.PrincetonInstruments.picam.TFrameInfo attribute), 827	TLimitSwitchParams (class in py-lablib.devices.Trinamic.base), 971	
timestamp_end_ns	(py-lablib.devices.Photometrics.pvcam.TFrameInfo attribute), 771	tmatr (pylablib.core.dataproc.ctransform_fallback.CLinear2DTransform property), 134	
timestamp_long	(pylablib.devices.SiliconSoftware.fgrab.TFrameInfo attribute), 841	TMCM1110 (class in pylablib.devices.Trinamic.base), 972	
timestamp_start	(py-lablib.devices.PrincetonInstruments.picam.TFrameInfo attribute), 827	TMCMx110 (class in pylablib.devices.Trinamic.base), 976	
timestamp_start_ns	(py-lablib.devices.Photometrics.pvcam.TFrameInfo attribute), 771	TMiscFramesStatus (class in py-lablib.devices.Andor.AndorSDK3), 536	
timestamp_us	(pylablib.devices.DCAM.DCAM.TFrameInfo attribute), 615	TModbusFrame (class in py-lablib.devices.Modbus.modbus), 715	
TimeTracker	(class in pylablib.core.utils.general), 431	TMotorInfo (class in pylablib.devices.Thorlabs.elliptec), 912	
timing()	(in module pylablib.core.utils.general), 432	TMoveParams (class in pylablib.devices.Standa.base), 877	
TInterbusTelegram	(class in py-lablib.devices.NKT.interbus), 725	TMulticast (class in py-lablib.core.thread.multicast_pool), 364	
TInternalBufferStatus	(class in py-lablib.devices.PCO.SC2), 755	to_alias() (pylablib.core.devio.interface.EnumParameterClass method), 201	
TTTR90Status	(class in pylablib.devices.Leybold.base), 687	to_alias() (pylablib.core.devio.interface.FunctionParameterClass method), 201	
TJogParams	(class in pylablib.devices.Thorlabs.kinesis), 919	to_alias() (pylablib.core.devio.interface.ICheckingParameterClass method), 198	
TJoystickEvent	(class in py-lablib.devices.Windows.joystick), 987	to_alias() (pylablib.core.devio.interface.IEnumParameterClass method), 199	
TJoystickEventEx	(class in py-lablib.devices.Windows.joystick), 987	to_alias() (pylablib.core.devio.interface.RangeParameterClass method), 199	
TKCubeTrigTOParams	(class in py-lablib.devices.Thorlabs.kinesis), 920	to_callable() (in module py-lablib.core.dataproc.callable), 133	
TKCubeTrigPosParams	(class in py-lablib.devices.Thorlabs.kinesis), 920	to_desc() (pylablib.core.devio.data_format.DataFormat method), 193	
TKJL3000DeviceInfo	(class in py-lablib.devices.KJL.base), 663	to_dict() (in module pylablib.core.utils.general), 426	
TLakeshore218AnalogSettings	(class in py-lablib.devices.Lakeshore.base), 671	to_dict() (pylablib.core.fileio.dict_entry.ExpandedContainerDictionaryEntry method), 210	
TLakeshore218CurveHeader	(class in py-lablib.devices.Lakeshore.base), 672	to_dict() (pylablib.core.fileio.dict_entry.ExternalBinTableDictionaryEntry method), 207	
		to_dict() (pylablib.core.fileio.dict_entry.ExternalNumpyDictionaryEntry method), 210	
		to_dict() (pylablib.core.fileio.dict_entry.ExternalTextTableDictionaryEntry method), 207	
		to_dict() (pylablib.core.fileio.dict_entry.IDictionaryEntry	

- method), 204
- to\_dict() (pylablib.core.fileio.dict\_entry.IExternalFileDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 208
- to\_dict() (pylablib.core.fileio.dict\_entry.IExternalTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 206
- to\_dict() (pylablib.core.fileio.dict\_entry.InlineTableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 205
- to\_dict() (pylablib.core.fileio.dict\_entry.ITableDictionaryEntry (class in pylablib.core.fileio.dict\_entry), 205
- to\_double\_index() (in module pylablib.core.utils.indexing), 434
- to\_Pa() (pylablib.devices.Agilent.pressure.XGS600 (class in pylablib.devices.Agilent.pressure), 506
- to\_Pa() (pylablib.devices.Pfeiffer.base.TPG260 (class in pylablib.devices.Pfeiffer.base), 764
- to\_pairs\_list() (in module pylablib.core.utils.general), 426
- to\_path() (pylablib.core.fileio.location.LocationName (class in pylablib.core.fileio.location), 217
- to\_predicate() (in module pylablib.core.utils.general), 425
- to\_range() (in module pylablib.core.utils.indexing), 433
- to\_range() (in module pylablib.core.utils.string), 452
- to\_string() (in module pylablib.core.utils.string), 451
- to\_string() (pylablib.core.fileio.location.LocationName (class in pylablib.core.fileio.location), 217
- to\_struct() (pylablib.core.utils.ctypes\_wrap.CStructWrapper (class in pylablib.core.utils.ctypes\_wrap), 375
- to\_value() (pylablib.core.devio.interface.EnumParameterClass (class in pylablib.core.devio.interface), 201
- to\_value() (pylablib.core.devio.interface.FunctionParameterClass (class in pylablib.core.devio.interface), 201
- to\_value() (pylablib.core.devio.interface.ICheckingParameterClass (class in pylablib.core.devio.interface), 198
- to\_value() (pylablib.core.devio.interface.IEnumParameterClass (class in pylablib.core.devio.interface), 199
- to\_value() (pylablib.core.devio.interface.RangeParameterClass (class in pylablib.core.devio.interface), 198
- ToggleButton (class in pylablib.core.gui.widgets.button), 232
- ToolButtonValueHandler (class in pylablib.core.gui.value\_handling), 322
- tooltip (pylablib.devices.Basler.pylon.BaslerPylonAttribute (class in pylablib.devices.Basler.pylon), 576
- tooltip (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute (class in pylablib.devices.IMAQdx.IMAQdx), 649
- top (pylablib.devices.interface.camera.TFramePosition (class in pylablib.devices.interface.camera), 989
- toploopSlot() (in module pylablib.core.thread.controller), 341
- topological\_order() (in module pylablib.core.utils.general), 427
- TopticaBackendError, 968
- TopticaError, 968
- TopticaIbeam (class in pylablib.devices.Toptica.ibeam), 969
- TopticaParameters (class in pylablib.devices.Andor.Shamrock), 544
- touch() (in module pylablib.core.utils.files), 412
- TOutputLimits (class in pylablib.devices.ElektroAutomatik.base), 622
- TPG260 (class in pylablib.devices.Pfeiffer.base), 764
- TPiezoetDriveParameters (class in pylablib.devices.Sirah.Matisse), 855
- TPiezoetFeedbackParameters (class in pylablib.devices.Sirah.Matisse), 855
- TPiezoetFeedforwardParameters (class in pylablib.devices.Sirah.Matisse), 855
- TPipeMsg (class in pylablib.core.utils.ipc), 435
- TPMDeviceInfo (class in pylablib.devices.Thorlabs.misc), 945
- TPMSensorInfo (class in pylablib.devices.Thorlabs.misc), 945
- TPolCtlParams (class in pylablib.devices.Thorlabs.kinesis), 919
- TPowerParams (class in pylablib.devices.Standa.base), 877
- TPZMotorDriveParams (class in pylablib.devices.Thorlabs.kinesis), 920
- TPZMotorJogParams (class in pylablib.devices.Thorlabs.kinesis), 920
- TQuadDetectorOutputParams (class in pylablib.devices.Thorlabs.kinesis), 942
- TQuadDetectorPIDParams (class in pylablib.devices.Thorlabs.kinesis), 941
- TQuadDetectorReadings (class in pylablib.devices.Thorlabs.kinesis), 942
- TQuadDetectorSetpoint (class in pylablib.devices.Thorlabs.kinesis), 942
- TRangeInfo (class in pylablib.devices.Ophir.base), 751
- transfer() (in module pylablib.core.utils.rpyc\_utils), 446
- transfer() (pylablib.core.utils.rpyc\_utils.DeviceService (class in pylablib.core.utils.rpyc\_utils), 447
- transfer() (pylablib.core.utils.rpyc\_utils.SocketTunnelService (class in pylablib.core.utils.rpyc\_utils), 447
- transfer\_missed (pylablib.devices.uc480.uc480.TAcquiredFramesStatus (class in pylablib.devices.uc480.uc480), 1023
- transit\_time (pylablib.devices.Thorlabs.kinesis.TFlipperParameters (class in pylablib.devices.Thorlabs.kinesis), 924
- translate\_string\_filter() (in module pylablib.core.utils.string), 449
- transpose() (pylablib.core.dataproc.ctransform\_fallback.CLinear2DTransform (class in pylablib.core.dataproc.ctransform\_fallback), 134
- travel (pylablib.devices.Thorlabs.elliptec.TDeviceInfo (class in pylablib.devices.Thorlabs.elliptec), 912

TRawParameterValue (class in py-lablib.core.devio.interface), 202	TScanMode (class in pylablib.devices.Sirah.Matisse), 856
TReadoutInfo (class in py-lablib.devices.Photometrics.pvcam), 771	TScanMoveParams (class in py-lablib.devices.SmarAct.MCS2), 869
TRefcellWaveformParameters (class in py-lablib.devices.Sirah.Matisse), 856	TScanParameters (class in py-lablib.devices.Sirah.Matisse), 856
trig1_mode (pylablib.devices.Thorlabs.kinesis.TKCubeTrigIOParameters attribute), 920	TSensorInfo (class in py-lablib.devices.Thorlabs.TLCamera), 903
trig1_pol (pylablib.devices.Thorlabs.kinesis.TKCubeTrigIOParameters attribute), 920	TShmemVarDesc (class in pylablib.core.utils.ipc), 436
trig2_mode (pylablib.devices.Thorlabs.kinesis.TKCubeTrigIOParameters attribute), 920	TSlowPiezoCtlParameters (class in py-lablib.devices.Sirah.Matisse), 855
trig2_pol (pylablib.devices.Thorlabs.kinesis.TKCubeTrigIOParameters attribute), 920	TStatus (class in py-lablib.devices.ElektroAutomatik.base), 622
trigger() (pylablib.core.utils.general.Countdown method), 429	TStatusLine (class in pylablib.devices.AlliedVision.Bonito), 521
trim_frames() (in module py-lablib.devices.interface.camera), 994	TStatusLineDescription (class in py-lablib.devices.interface.camera), 1019
trim_frames_range() (py-lablib.devices.interface.camera.FrameCounter method), 995	TStepMoveParams (class in py-lablib.devices.SmarAct.MCS2), 869
TrinamicBackendError, 971	TStepperMotorCalibration (class in py-lablib.devices.Standa.base), 876
TrinamicError, 971	TTemperatures (class in py-lablib.devices.LaserQuantum.base), 682
TrinamicTimeoutError, 971	TTemperatures (class in py-lablib.devices.Toptica.ibeam), 968
TROIConstraints (class in py-lablib.devices.PrincetonInstruments.picam), 824	TThinCtlParameters (class in py-lablib.devices.Sirah.Matisse), 855
truncate_roi_axis() (in module py-lablib.devices.interface.camera), 1010	TTimer (class in pylablib.core.gui.widgets.container), 235
truncate_trace() (in module py-lablib.core.dataproc.fourier), 144	TTimerEvent (class in py-lablib.core.gui.widgets.container), 235
truncate_value() (py-lablib.devices.Andor.AndorSDK3.AndorSDK3Attribute method), 536	TTimestamp (class in pylablib.devices.uc480.uc480), 1023
truncate_value() (py-lablib.devices.Basler.pylon.BaslerPylonAttribute method), 577	TTMCM1110ReplyData (class in py-lablib.devices.Trinamic.base), 972
truncate_value() (py-lablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute method), 650	TTPG260GaugeControlSettings (class in py-lablib.devices.Pfeiffer.base), 764
truncate_value() (py-lablib.devices.Photometrics.pvcam.PvcamAttribute method), 771	TTPG260SwitchSettings (class in py-lablib.devices.Pfeiffer.base), 764
truncate_value() (py-lablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute method), 781	TTriggerParameters (class in py-lablib.devices.Tektronix.base), 881
truncate_value() (py-lablib.devices.PrincetonInstruments.picam.PicamAttribute method), 827	tune_etalon() (pylablib.devices.M2.solstis.Solstis method), 702
truncate_value() (py-lablib.devices.SiliconSoftware.fgrab.FGGrabAttribute method), 840	tune_laser_resonator() (py-lablib.devices.M2.solstis.Solstis method), 703
try_import_cext() (in module py-lablib.core.utils.cext_tools), 372	tune_reference_cavity() (py-lablib.devices.M2.solstis.Solstis method), 703
	tune_to() (pylablib.devices.Sirah.tuner.MatisseTuner method), 867
	tune_to_gen() (pylablib.devices.Sirah.tuner.MatisseTuner method), 866
	tunnel_recv() (pylablib.core.utils.rpyc_utils.DeviceService

- method), 447
- tunnel\_recv() (pylablib.core.utils.rpyc\_utils.SocketTunnelService method), 447
- tunnel\_send() (pylablib.core.utils.rpyc\_utils.DeviceService method), 447
- tunnel\_send() (pylablib.core.utils.rpyc\_utils.SocketTunnelService method), 447
- tup() (pylablib.core.dataproc.image.ROI method), 148
- tup() (pylablib.core.dataproc.utils.Range method), 164
- tup() (pylablib.core.utils.ctypes\_wrap.CStructWrapper method), 375
- tup() (pylablib.core.utils.indexing.IIndex method), 433
- tup() (pylablib.core.utils.indexing.ListIndex method), 434
- tup() (pylablib.core.utils.indexing.ListIndexNoSlice method), 434
- tup() (pylablib.core.utils.indexing.NumpyIndex method), 434
- tup\_struct() (pylablib.core.utils.ctypes\_wrap.CStructWrapper class method), 375
- TUpdateValue (class in pylablib.devices.Leybold.base), 685
- TVC880Reading (class in pylablib.devices.Voltcraft.multimeter), 984
- TVelocityParams (class in pylablib.devices.Thorlabs.kinesis), 919
- TVelocityParams (class in pylablib.devices.Trinamic.base), 971
- TVoltageOutputClockParameters (class in pylablib.devices.NI.daq), 718
- TWavelengthInfo (class in pylablib.devices.Ophir.base), 751
- TWidgetLocation (class in pylablib.core.gui.utils), 309
- TWorkHours (class in pylablib.devices.LaserQuantum.base), 682
- TWorkHours (class in pylablib.devices.LighthousePhotonics.base), 690
- TWorkHours (class in pylablib.devices.Toptica.ibeam), 968
- TXGS600DeviceInfo (class in pylablib.devices.Agilent.pressure), 505
- typ (pylablib.devices.NKT.interbus.TInterbusTelegram attribute), 725
- typ (pylablib.devices.Voltcraft.multimeter.VC880.TMessage attribute), 985
- type (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 649
- type (pylablib.devices.Ophir.base.THeadInfo attribute), 750
- type (pylablib.devices.PhotonFocus.PhotonFocus.TCameraInfo attribute), 780
- type (pylablib.devices.Thorlabs.misc.TPMSensorInfo attribute), 945
- ## U
- UC480Camera (class in pylablib.devices.uc480.uc480), 1024
- uid (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute), 839
- UIDGenerator (class in pylablib.core.utils.general), 429
- unescape\_string() (in module pylablib.core.utils.string), 452
- uninit\_result (pylablib.devices.utils.load\_lib.TLibraryCloseResult attribute), 1033
- unique\_class() (in module pylablib.core.utils.general), 427
- unique\_slices() (in module pylablib.core.dataproc.utils), 163
- unit (pylablib.devices.DCAM.DCAM.DCAMAttribute attribute), 614
- unit (pylablib.devices.Voltcraft.multimeter.TVC880Reading attribute), 985
- units (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576
- units (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649
- unity() (in module pylablib.core.utils.numerical), 444
- unload\_all() (in module pylablib), 1034
- unload\_package\_modules() (in module pylablib.core.utils.module), 438
- unlock() (pylablib.core.devio.comm\_backend.FT232DeviceBackend method), 180
- unlock() (pylablib.core.devio.comm\_backend.HIDDeviceBackend method), 189
- unlock() (pylablib.core.devio.comm\_backend.ICommBackendWrapper method), 193
- unlock() (pylablib.core.devio.comm\_backend.IDeviceCommBackend method), 171
- unlock() (pylablib.core.devio.comm\_backend.NetworkDeviceBackend method), 183
- unlock() (pylablib.core.devio.comm\_backend.PyUSBDeviceBackend method), 186
- unlock() (pylablib.core.devio.comm\_backend.RecordedDeviceBackend method), 191
- unlock() (pylablib.core.devio.comm\_backend.SerialDeviceBackend method), 178
- unlock() (pylablib.core.devio.comm\_backend.VisaDeviceBackend method), 173
- unlock() (pylablib.core.devio.SCPI.SCPIDevice method), 168
- unlock() (pylablib.devices.Agilent.pressure.XGS600 method), 507
- unlock() (pylablib.devices.Arduino.base.IArduinoDevice method), 565
- unlock() (pylablib.devices.Attocube.anc300.ANC300 method), 569
- unlock() (pylablib.devices.Attocube.anc350.ANC350 method), 573



- `unlock()` (`pylablib.devices.AWG.generic.GenericAWG` method), 460
- `unlock()` (`pylablib.devices.AWG.specific.Agilent33220A` method), 473
- `unlock()` (`pylablib.devices.AWG.specific.Agilent33500` method), 467
- `unlock()` (`pylablib.devices.AWG.specific.InstekAFG2000` method), 485
- `unlock()` (`pylablib.devices.AWG.specific.InstekAFG2225` method), 479
- `unlock()` (`pylablib.devices.AWG.specific.RigolDG1000` method), 504
- `unlock()` (`pylablib.devices.AWG.specific.RSInstekAFG21000` method), 491
- `unlock()` (`pylablib.devices.AWG.specific.TektronixAFG1000` method), 497
- `unlock()` (`pylablib.devices.Conrad.base.RelayBoard` method), 599
- `unlock()` (`pylablib.devices.Cryocon.base.Cryocon1x` method), 602
- `unlock()` (`pylablib.devices.Cryomagnetics.base.LM500` method), 607
- `unlock()` (`pylablib.devices.Cryomagnetics.base.LM510` method), 611
- `unlock()` (`pylablib.devices.ElektroAutomatik.base.PS2000` method), 625
- `unlock()` (`pylablib.devices.Hubner.Cobolt.Cobolt` method), 633
- `unlock()` (`pylablib.devices.Keithley.mmultimeter.Keithley216` method), 670
- `unlock()` (`pylablib.devices.KJL.base.KJL300` method), 665
- `unlock()` (`pylablib.devices.Lakeshore.base.Lakeshore218` method), 676
- `unlock()` (`pylablib.devices.Lakeshore.base.Lakeshore370` method), 681
- `unlock()` (`pylablib.devices.LaserQuantum.base.Finesse` method), 684
- `unlock()` (`pylablib.devices.Leybold.base.GenericITR` method), 687
- `unlock()` (`pylablib.devices.Leybold.base.ITR90` method), 689
- `unlock()` (`pylablib.devices.LighthousePhotonics.base.Sprout` method), 692
- `unlock()` (`pylablib.devices.Lumel.base.LumelRE72Controller` method), 695
- `unlock()` (`pylablib.devices.Modbus.modbus.GenericModbusRTUDevice` method), 717
- `unlock()` (`pylablib.devices.Newport.picomotor.Picomotor8601` method), 739
- `unlock()` (`pylablib.devices.NKT.interbus.GenericInterbusDevice` method), 727
- `unlock()` (`pylablib.devices.NKT.interbus.InterbusSystem` method), 735
- `unlock()` (`pylablib.devices.Omron.base.OmronE5xCCController` method), 749
- `unlock()` (`pylablib.devices.Ophir.base.OphirDevice` method), 750
- `unlock()` (`pylablib.devices.Ophir.base.VegaPowerMeter` method), 754
- `unlock()` (`pylablib.devices.OZOptics.base.DD100` method), 744
- `unlock()` (`pylablib.devices.OZOptics.base.EPC04` method), 746
- `unlock()` (`pylablib.devices.OZOptics.base.OZOpticsDevice` method), 741
- `unlock()` (`pylablib.devices.OZOptics.base.TF100` method), 743
- `unlock()` (`pylablib.devices.Pfeiffer.base.DPG202` method), 769
- `unlock()` (`pylablib.devices.Pfeiffer.base.TPG260` method), 767
- `unlock()` (`pylablib.devices.PhysikInstrumente.base.GenericPIController` method), 816
- `unlock()` (`pylablib.devices.PhysikInstrumente.base.PIE515` method), 822
- `unlock()` (`pylablib.devices.PhysikInstrumente.base.PIE516` method), 819
- `unlock()` (`pylablib.devices.Rigol.power_supply.DP1116A` method), 837
- `unlock()` (`pylablib.devices.Sirah.Matisse.SirahMatisse` method), 862
- `unlock()` (`pylablib.devices.Standa.base.Standa8SMC` method), 880
- `unlock()` (`pylablib.devices.Tektronix.base.DPO2000` method), 901
- `unlock()` (`pylablib.devices.Tektronix.base.ITektronixScope` method), 887
- `unlock()` (`pylablib.devices.Tektronix.base.TDS2000` method), 894
- `unlock()` (`pylablib.devices.Thorlabs.elliptec.ElliptecMotor` method), 915
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.BasicKinesisDevice` method), 919
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.KinesisDevice` method), 923
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.KinesisMotor` method), 934
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoController` method), 941
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor` method), 938
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.KinesisQuadDetector` method), 945
- `unlock()` (`pylablib.devices.Thorlabs.kinesis.MFF` method), 927
- `unlock()` (`pylablib.devices.Thorlabs.misc.GenericPM` method), 949

`unlock()` (`pylablib.devices.Thorlabs.misc.PM160` method), 953  
`unlock()` (`pylablib.devices.Thorlabs.serial.FW` method), 960  
`unlock()` (`pylablib.devices.Thorlabs.serial.FWv1` method), 963  
`unlock()` (`pylablib.devices.Thorlabs.serial.MDT69xA` method), 967  
`unlock()` (`pylablib.devices.Thorlabs.serial.ThorlabsSerial` method), 956  
`unlock()` (`pylablib.devices.Toptica.ibeam.TopticaIBeam` method), 970  
`unlock()` (`pylablib.devices.Trinamic.base.TMCM1110` method), 976  
`unlock()` (`pylablib.devices.Trinamic.base.TMCMx110` method), 980  
`unlock()` (`pylablib.devices.Voltcraft.multimeter.VC7055` method), 983  
`unlock()` (`pylablib.devices.Voltcraft.multimeter.VC880` method), 986  
`unlock_all()` (`pylablib.devices.Sirah.tuner.MatisseTuner` method), 866  
`unlock_etalon()` (`pylablib.devices.M2.solstis.Solstis` method), 703  
`unlock_reference_cavity()` (`pylablib.devices.M2.solstis.Solstis` method), 703  
`unpack_int()` (in module `pylablib.core.utils.strpack`), 454  
`unpack_numpy_u12bit()` (in module `pylablib.core.utils.strpack`), 454  
`unpack_uint()` (in module `pylablib.core.utils.strpack`), 453  
`unread()` (`pylablib.devices.interface.camera.TFramesStatus` attribute), 989  
`unschedule()` (`pylablib.core.thread.callsync.QQueueLengthScheduler` method), 337  
`unschedule()` (`pylablib.core.thread.callsync.QQueueScheduler` method), 335  
`unschedule()` (`pylablib.core.thread.callsync.QQueueSizeLimitScheduler` method), 339  
`unschedule()` (`pylablib.core.thread.controller.QTaskThread` method), 351  
`unsubscribe()` (`pylablib.core.thread.controller.QTaskThread` method), 363  
`unsubscribe()` (`pylablib.core.thread.controller.QThreadController` method), 346  
`unsubscribe()` (`pylablib.core.thread.multicast_pool.MulticastPool` method), 365  
`unwrap_mod_data()` (in module `pylablib.core.dataproc.utils`), 165  
`unzip_file()` (in module `pylablib.core.utils.files`), 419  
`unzip_folder()` (in module `pylablib.core.utils.files`), 419  
`update()` (`pylablib.core.utils.dictionary.Dictionary` method), 382  
`update()` (`pylablib.core.utils.dictionary.DictionaryPointer` method), 392  
`update()` (`pylablib.core.utils.dictionary.FilterTree` method), 409  
`update()` (`pylablib.core.utils.dictionary.PrefixTree` method), 401  
`update_acquired_frames()` (`pylablib.devices.interface.camera.FrameCounter` method), 994  
`update_attribute_value()` (`pylablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera` method), 782  
`update_attribute_value()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCamera` method), 812  
`update_attribute_value()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMAQCamera` method), 796  
`update_attribute_value()` (`pylablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCamera` method), 805  
`update_available_axes()` (`pylablib.devices.Attocube.anc300.ANC300` method), 566  
`update_connected_addrs()` (`pylablib.devices.Thorlabs.elliptec.ElliptecMotor` method), 912  
`update_fit_parameters()` (`pylablib.core.dataproc.fitting.Fitter` method), 142  
`update_fixed_parameters()` (`pylablib.core.dataproc.fitting.Fitter` method), 142  
`update_full_data()` (`pylablib.devices.PCO.SC2.PCOS2Camera` method), 756  
`update_indicators()` (`pylablib.core.gui.value_handling.GUIValues` method), 329  
`update_indicators()` (`pylablib.core.gui.widgets.container.IQContainer` method), 238  
`update_indicators()` (`pylablib.core.gui.widgets.container.IQWidgetContainer` method), 245  
`update_indicators()` (`pylablib.core.gui.widgets.container.QContainer` method), 240  
`update_indicators()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 259  
`update_indicators()` (`pylablib.core.gui.widgets.container.QDialogContainer` method), 259

`lablib.core.gui.widgets.container.QFrameContainer` method), 701  
`method`), 254 `update_reports()` (`pylablib.devices.M2.solstis.Solstis`  
`update_indicators()` (`py-` method), 707  
`lablib.core.gui.widgets.container.QGroupBoxContainer` `update_sensor_modes()` (`py-`  
`method`), 264 `lablib.devices.Thorlabs.misc.GenericPM`  
`update_indicators()` (`py-` method), 946  
`lablib.core.gui.widgets.container.QScrollAreaContainer` `update_sensor_modes()` (`py-`  
`method`), 271 `lablib.devices.Thorlabs.misc.PM160` method),  
`update_indicators()` (`py-` 953  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QStatusWidget` (`py-`  
`method`), 269 `lablib.core.thread.controller.QTaskThread`  
`update_indicators()` (`py-` method), 354  
`lablib.core.gui.widgets.container.QTabContainer` `update_status_line()` (`py-`  
`method`), 274 `lablib.core.gui.widgets.param_table.StatusTable`  
`update_indicators()` (`py-` method), 296  
`lablib.core.gui.widgets.container.QWidgetContainer` `update_value()` (`pylablib.core.gui.value_handling.GUIValues`  
`method`), 250 `method`), 329  
`update_indicators()` (`py-` `update_value()` (`pylablib.core.gui.widgets.container.IQContainer`  
`lablib.core.gui.widgets.param_table.ParamTable` method), 238  
`method`), 292 `update_value()` (`pylablib.core.gui.widgets.container.IQWidgetContainer`  
`update_indicators()` (`py-` method), 245  
`lablib.core.gui.widgets.param_table.StatusTable` `update_value()` (`pylablib.core.gui.widgets.container.QContainer`  
`method`), 306 `method`), 241  
`update_limits()` (`py-` `update_value()` (`pylablib.core.gui.widgets.container.QDialogContainer`  
`lablib.devices.Andor.AndorSDK3.AndorSDK3Attribute` method), 259  
`method`), 536 `update_value()` (`pylablib.core.gui.widgets.container.QFrameContainer`  
`update_limits()` (`py-` method), 255  
`lablib.devices.Basler.pylon.BaslerPylonAttribute` `update_value()` (`pylablib.core.gui.widgets.container.QGroupBoxContainer`  
`method`), 577 `method`), 264  
`update_limits()` (`py-` `update_value()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer`  
`lablib.devices.DCAM.DCAM.DCAMAttribute` method), 271  
`method`), 614 `update_value()` (`pylablib.core.gui.widgets.container.QScrollAreaContainer`  
`update_limits()` (`py-` method), 269  
`lablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute` `update_value()` (`pylablib.core.gui.widgets.container.QTabContainer`  
`method`), 650 `method`), 274  
`update_limits()` (`py-` `update_value()` (`pylablib.core.gui.widgets.container.QWidgetContainer`  
`lablib.devices.Photometrics.pvcam.PvcamAttribute` method), 250  
`method`), 771 `update_value()` (`pylablib.core.gui.widgets.param_table.ParamTable`  
`update_limits()` (`py-` method), 291  
`lablib.devices.PhotonFocus.PhotonFocus.PFCameraAttribute` `update_value()` (`pylablib.core.gui.widgets.param_table.StatusTable`  
`method`), 781 `method`), 306  
`update_limits()` (`py-` `updated()` (`pylablib.core.utils.dictionary.Dictionary`  
`lablib.devices.PrincetonInstruments.picam.PicamAttribute` method), 382  
`method`), 827 `updated()` (`pylablib.core.utils.dictionary.DictionaryPointer`  
`update_limits()` (`py-` method), 393  
`lablib.devices.SiliconSoftware.fgrab.FGrabAttribute` `updated()` (`pylablib.core.utils.dictionary.FilterTree`  
`method`), 840 `method`), 410  
`update_properties()` (`py-` `updated()` (`pylablib.core.utils.dictionary.PrefixShortcutTree`  
`lablib.devices.Andor.AndorSDK3.AndorSDK3Attribute` method), 411  
`method`), 535 `updated()` (`pylablib.core.utils.dictionary.PrefixTree`  
`update_reports()` (`py-` method), 402  
`lablib.devices.M2.base.ICEBlocDevice` `upper_limit` (`pylablib.devices.Sirah.Matisse.TRefCellWaveformParameters`  
`method`), 696 `attribute`), 856  
`update_reports()` (`pylablib.devices.M2.emm.EMM` `upper_limit` (`pylablib.devices.Sirah.Matisse.TScanParameters`

attribute), 856

usb\_version (pylablib.devices.uc480.uc480.TDeviceInfo attribute), 1023

use\_parameters() (in module py-lablib.core.devio.interface), 202

use\_xarg() (pylablib.core.dataproc.fitting.Fitter method), 142

user\_name (pylablib.devices.Basler.pylon.TCameraInfo attribute), 575

user\_name (pylablib.devices.Basler.pylon.TDeviceInfo attribute), 577

using\_channel() (py-lablib.devices.Thorlabs.kinesis.KinesisDevice method), 921

using\_channel() (py-lablib.devices.Thorlabs.kinesis.KinesisMotor method), 934

using\_channel() (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoController method), 941

using\_channel() (py-lablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method), 938

using\_channel() (py-lablib.devices.Thorlabs.kinesis.MFF method), 927

using\_default\_addr() (py-lablib.devices.Thorlabs.elliptec.ElliptecMotor method), 913

using\_default\_axis() (py-lablib.devices.SmarAct.MCS2.MCS2 method), 870

using\_device() (pylablib.core.devio.interface.CombinedParameterClass method), 202

using\_device() (pylablib.core.devio.interface.EnumParameterClass method), 201

using\_device() (pylablib.core.devio.interface.FunctionParameterClass method), 201

using\_device() (pylablib.core.devio.interface.ICheckingParameterClass method), 198

using\_device() (pylablib.core.devio.interface.IEnumParameterClass method), 200

using\_device() (pylablib.core.devio.interface.IParameterClass method), 197

using\_device() (pylablib.core.devio.interface.RangeParameterClass method), 199

using\_layout() (pylablib.core.gui.widgets.container.IQWidgetContainer method), 245

using\_layout() (pylablib.core.gui.widgets.container.QDialogContainer method), 259

using\_layout() (pylablib.core.gui.widgets.container.QFrameContainer method), 255

using\_layout() (pylablib.core.gui.widgets.container.QGroupBoxContainer method), 264

using\_layout() (pylablib.core.gui.widgets.container.QScrollAreaContainer method), 269

using\_layout() (pylablib.core.gui.widgets.container.QWidgetContainer method), 250

using\_layout() (pylablib.core.gui.widgets.layout\_manager.IQLayoutManager method), 280

using\_layout() (pylablib.core.gui.widgets.layout\_manager.QLayoutManager method), 284

using\_layout() (pylablib.core.gui.widgets.param\_table.ParamTable method), 295

using\_layout() (pylablib.core.gui.widgets.param\_table.StatusTable method), 306

using\_layout\_tags() (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 245

using\_layout\_tags() (py-lablib.core.gui.widgets.container.QDialogContainer method), 259

using\_layout\_tags() (py-lablib.core.gui.widgets.container.QFrameContainer method), 255

using\_layout\_tags() (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 264

using\_layout\_tags() (py-lablib.core.gui.widgets.container.QScrollAreaContainer.QContainer method), 269

using\_layout\_tags() (py-lablib.core.gui.widgets.container.QWidgetContainer method), 250

using\_layout\_tags() (py-lablib.core.gui.widgets.layout\_manager.IQLayoutManagedWidget method), 280

using\_layout\_tags() (py-lablib.core.gui.widgets.layout\_manager.QLayoutManagedWidget method), 284

using\_new\_layout() (py-lablib.core.gui.widgets.param\_table.ParamTable method), 295

using\_new\_layout() (py-lablib.core.gui.widgets.param\_table.StatusTable method), 306

using\_new\_method() (in module pylablib.core.utils.general), 425

using\_new\_sublayout() (py-lablib.core.gui.widgets.container.IQWidgetContainer method), 245

using\_new\_sublayout() (py-lablib.core.gui.widgets.container.QDialogContainer method), 259

using\_new\_sublayout() (py-lablib.core.gui.widgets.container.QFrameContainer method), 255

using\_new\_sublayout() (py-lablib.core.gui.widgets.container.QGroupBoxContainer method), 264



`lablib.core.gui.widgets.container.QGroupBoxContainer` method), 473  
`method`), 264 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.Agilent33500`  
`lablib.core.gui.widgets.container.QScrollAreaContainer.QScrollAreaWidget`  
`method`), 269 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.InstekAFG2000`  
`lablib.core.gui.widgets.container.QWidgetContainer` method), 485  
`method`), 250 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.InstekAFG2225`  
`lablib.core.gui.widgets.layout_manager.IQLayoutManagedWidget` method), 479  
`method`), 280 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.RigolDG1000`  
`lablib.core.gui.widgets.layout_manager.QLayoutManagedWidget` method), 504  
`method`), 284 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.RSInstekAFG21000`  
`lablib.core.gui.widgets.param_table.ParamTable` method), 491  
`method`), 285 `using_write_buffer()` (py-  
`using_new_sublayout()` (py- `lablib.devices.AWG.specific.TektronixAFG1000`  
`lablib.core.gui.widgets.param_table.StatusTable` method), 497  
`method`), 306 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Cryocon.base.Cryocon1x`  
`lablib.core.devio.comm_backend.FT232DeviceBackend` method), 602  
`method`), 180 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Cryomagnetics.base.LM500`  
`lablib.core.devio.comm_backend.HIDDeviceBackend` method), 607  
`method`), 189 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Cryomagnetics.base.LM510`  
`lablib.core.devio.comm_backend.IDeviceCommBackend` method), 611  
`method`), 171 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Keithley.multimeter.Keithley2110`  
`lablib.core.devio.comm_backend.NetworkDeviceBackend` method), 670  
`method`), 183 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Lakeshore.base.Lakeshore218`  
`lablib.core.devio.comm_backend.PyUSBDeviceBackend` method), 676  
`method`), 186 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Lakeshore.base.Lakeshore370`  
`lablib.core.devio.comm_backend.RecordedDeviceBackend` method), 681  
`method`), 191 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.PhysikInstrumente.base.PIE515`  
`lablib.core.devio.comm_backend.SerialDeviceBackend` method), 822  
`method`), 178 `using_write_buffer()` (py-  
`using_timeout()` (py- `lablib.devices.Rigol.power_supply.DP1116A`  
`lablib.core.devio.comm_backend.VisaDeviceBackend` method), 837  
`method`), 175 `using_write_buffer()` (py-  
`using_timeout()` (pylablib.core.utils.net.ClientSocket `lablib.devices.Sirah.Matisse.SirahMatisse`  
`method`), 442 `method`), 862  
`using_write_buffer()` (py- `using_write_buffer()` (py-  
`lablib.core.devio.SCPI.SCPIDevice` method), `lablib.devices.Tektronix.base.DPO2000`  
166 `method`), 901  
`using_write_buffer()` (py- `using_write_buffer()` (py-  
`lablib.devices.AWG.generic.GenericAWG` `lablib.devices.Tektronix.base.ITektronixScope`  
`method`), 460 `method`), 887  
`using_write_buffer()` (py- `using_write_buffer()` (py-  
`lablib.devices.AWG.specific.Agilent33220A` `lablib.devices.Tektronix.base.TDS2000`

*method*), 894

`using_write_buffer()` (*pylablib.devices.Thorlabs.misc.GenericPM method*), 949

`using_write_buffer()` (*pylablib.devices.Thorlabs.misc.PM160 method*), 953

`using_write_buffer()` (*pylablib.devices.Thorlabs.serial.FW method*), 960

`using_write_buffer()` (*pylablib.devices.Thorlabs.serial.FWv1 method*), 963

`using_write_buffer()` (*pylablib.devices.Thorlabs.serial.MDT69xA method*), 967

`using_write_buffer()` (*pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface method*), 956

`using_write_buffer()` (*pylablib.devices.Voltcraft.multimeter.VC7055 method*), 983

`usteps_per_step` (*pylablib.devices.Standa.base.TStepperMotorCalibration attribute*), 877

## V

`value` (*pylablib.core.devio.interface.TRawParameterValue attribute*), 202

`value` (*pylablib.core.thread.multicast\_pool.TMulticast attribute*), 364

`value` (*pylablib.devices.Leybold.base.TUpdateValue attribute*), 685

`value` (*pylablib.devices.Trinamic.base.TTMCM1110ReplyData attribute*), 972

`value` (*pylablib.devices.Voltcraft.multimeter.TVC880Reading attribute*), 985

`value_access` (*pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute*), 825

`value_changed` (*pylablib.core.gui.widgets.button.ToggleButton attribute*), 232

`value_changed` (*pylablib.core.gui.widgets.button\_selector.ButtonSelector attribute*), 233

`value_changed` (*pylablib.core.gui.widgets.combo\_box.ComboBox attribute*), 235

`value_changed` (*pylablib.core.gui.widgets.edit.NumEdit attribute*), 276

`value_changed` (*pylablib.core.gui.widgets.edit.TextEdit attribute*), 275

`value_changed` (*pylablib.core.gui.widgets.label.EnumLabel attribute*), 278

`value_changed` (*pylablib.core.gui.widgets.label.NumLabel attribute*), 279

`value_changed` (*pylablib.core.gui.widgets.label.TextLabel attribute*), 277

`value_entered` (*pylablib.core.gui.widgets.edit.NumEdit attribute*), 276

`value_entered` (*pylablib.core.gui.widgets.edit.TextEdit attribute*), 275

`value_handler` (*pylablib.core.gui.widgets.param\_table.ParamTable.ParamTable attribute*), 285

`value_to_index()` (*pylablib.core.gui.widgets.button\_selector.ButtonSelector method*), 233

`value_to_index()` (*pylablib.core.gui.widgets.combo\_box.ComboBox method*), 234

`values` (*pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute attribute*), 535

`values` (*pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute*), 577

`values` (*pylablib.devices.DCAM.DCAM.DCAMAttribute attribute*), 614

`values` (*pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute*), 650

`values` (*pylablib.devices.Photometrics.pvcam.PvcamAttribute attribute*), 770

`values` (*pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute attribute*), 781

`values` (*pylablib.devices.PrincetonInstruments.picam.PicamAttribute attribute*), 827

`values` (*pylablib.devices.SiliconSoftware.fgrab.FGrabAttribute attribute*), 840

`values()` (*pylablib.core.utils.dictionary.Dictionary method*), 379

`values()` (*pylablib.core.utils.dictionary.DictionaryPointer method*), 393

`values()` (*pylablib.core.utils.dictionary.FilterTree method*), 410

`values()` (*pylablib.core.utils.dictionary.PrefixTree method*), 402

`VC7055` (*class in pylablib.devices.Voltcraft.multimeter*), 981

`VC880` (*class in pylablib.devices.Voltcraft.multimeter*), 985

`VC880.TMessage` (*class in pylablib.devices.Voltcraft.multimeter*), 985

`VC880.ParseError`, 984

`VegaPowerMeter` (*class in pylablib.devices.Ophir.base*), 751

`velocity` (*pylablib.devices.SmarAct.MCS2.TCLMoveParams attribute*), 869

`velocity` (*pylablib.devices.SmarAct.MCS2.TScanMoveParams attribute*), 869

`velocity` (*pylablib.devices.Thorlabs.kinesis.THomeParams attribute*), 919

`velocity` (*pylablib.devices.Thorlabs.kinesis.TPolCtlParams attribute*), 919

attribute), 919  
 velocity (pylablib.devices.Thorlabs.kinesis.TPZMotorDriver.attribute), 920  
 velocity (pylablib.devices.Thorlabs.kinesis.TPZMotorJog.attribute), 921  
 vendor (pylablib.devices.Basler.pylon.TCameraInfo attribute), 575  
 vendor (pylablib.devices.Basler.pylon.TDeviceInfo attribute), 577  
 vendor (pylablib.devices.DCAM.DCAM.TDeviceInfo attribute), 615  
 vendor (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 649  
 vendor (pylablib.devices.IMAQdx.IMAQdx.TDeviceInfo attribute), 650  
 vendor (pylablib.devices.Photometrics.pvcam.TDeviceInfo attribute), 771  
 vendor\_id (pylablib.core.devio.hid.TDeviceDescription attribute), 194  
 version (pylablib.core.devio.hid.TDeviceDescription attribute), 194  
 version (pylablib.devices.AlliedVision.Bonito.TDeviceInfo attribute), 507  
 version (pylablib.devices.Attocube.anc300.TDeviceInfo attribute), 566  
 version (pylablib.devices.IMAQdx.IMAQdx.TCameraInfo attribute), 649  
 version (pylablib.devices.LighthousePhotonics.base.TDeviceInfo attribute), 690  
 version (pylablib.devices.PhotonFocus.PhotonFocus.TCameraInfo attribute), 780  
 version (pylablib.devices.SiliconSoftware.fgrab.TFullAppletInfo attribute), 839  
 version (pylablib.devices.Toptica.ibeam.TDeviceInfo attribute), 968  
 viewitems() (pylablib.core.utils.dictionary.Dictionary method), 379  
 viewitems() (pylablib.core.utils.dictionary.DictionaryPointer method), 393  
 viewitems() (pylablib.core.utils.dictionary.FilterTree method), 410  
 viewitems() (pylablib.core.utils.dictionary.PrefixTree method), 402  
 viewkeys() (pylablib.core.utils.dictionary.Dictionary method), 380  
 viewkeys() (pylablib.core.utils.dictionary.DictionaryPointer method), 393  
 viewkeys() (pylablib.core.utils.dictionary.FilterTree method), 410  
 viewkeys() (pylablib.core.utils.dictionary.PrefixTree method), 402  
 viewvalues() (pylablib.core.utils.dictionary.Dictionary method), 380  
 viewvalues() (pylablib.core.utils.dictionary.DictionaryPointer method), 393  
 viewvalues() (pylablib.core.utils.dictionary.FilterTree method), 410  
 viewvalues() (pylablib.core.utils.dictionary.PrefixTree method), 402  
 virtual\_gui\_values() (in module pylablib.core.gui.value\_handling), 329  
 VirtualIndicatorHandler (in module pylablib.core.gui.value\_handling), 325  
 VirtualValueChangedSignal (class in pylablib.core.gui.value\_handling), 312  
 VirtualValueHandler (class in pylablib.core.gui.value\_handling), 312  
 VisaDeviceBackend (class in pylablib.core.devio.comm\_backend), 173  
 visibility (pylablib.devices.Basler.pylon.BaslerPylonAttribute attribute), 576  
 visibility (pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute attribute), 649  
 voltage (pylablib.devices.ElektroAutomatik.base.TOutputLimits attribute), 622

## W

wait() (pylablib.core.devio.SCPI.SCPIDevice method), 167  
 wait() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 331  
 wait() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331  
 wait() (pylablib.core.thread.notifier.ISkippableNotifier method), 366  
 wait() (pylablib.core.thread.synchronizing.QMultiThreadNotifier method), 368  
 wait() (pylablib.core.thread.synchronizing.QThreadNotifier method), 367  
 wait() (pylablib.devices.AWG.generic.GenericAWG method), 461  
 wait() (pylablib.devices.AWG.specific.Agilent33220A method), 473  
 wait() (pylablib.devices.AWG.specific.Agilent33500 method), 467  
 wait() (pylablib.devices.AWG.specific.InstekAFG2000 method), 485  
 wait() (pylablib.devices.AWG.specific.InstekAFG2225 method), 479  
 wait() (pylablib.devices.AWG.specific.RigolDG1000 method), 504  
 wait() (pylablib.devices.AWG.specific.RSInstekAFG21000 method), 491  
 wait() (pylablib.devices.AWG.specific.TektronixAFG1000 method), 498  
 wait() (pylablib.devices.Cryocon.base.Cryocon1x method), 602

<code>wait()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 607	<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.TektronixAFG1000</code> method), 498
<code>wait()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 611	<code>wait_dev()</code> ( <code>pylablib.devices.Cryocon.base.Cryocon1x</code> method), 603
<code>wait()</code> ( <code>pylablib.devices.interface.camera.FrameNotifier</code> method), 995	<code>wait_dev()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM500</code> method), 607
<code>wait()</code> ( <code>pylablib.devices.Keithley.multimeter.Keithley2110</code> method), 670	<code>wait_dev()</code> ( <code>pylablib.devices.Cryomagnetics.base.LM510</code> method), 612
<code>wait()</code> ( <code>pylablib.devices.Lakeshore.base.Lakeshore218</code> method), 676	<code>wait_dev()</code> ( <code>pylablib.devices.Keithley.multimeter.Keithley2110</code> method), 670
<code>wait()</code> ( <code>pylablib.devices.Lakeshore.base.Lakeshore370</code> method), 681	<code>wait_dev()</code> ( <code>pylablib.devices.Lakeshore.base.Lakeshore218</code> method), 676
<code>wait()</code> ( <code>pylablib.devices.PhysikInstrumente.base.PIE515</code> method), 823	<code>wait_dev()</code> ( <code>pylablib.devices.Lakeshore.base.Lakeshore370</code> method), 681
<code>wait()</code> ( <code>pylablib.devices.Rigol.power_supply.DP1116A</code> method), 837	<code>wait_dev()</code> ( <code>pylablib.devices.PhysikInstrumente.base.PIE515</code> method), 823
<code>wait()</code> ( <code>pylablib.devices.Sirah.Matisse.SirahMatisse</code> method), 863	<code>wait_dev()</code> ( <code>pylablib.devices.Rigol.power_supply.DP1116A</code> method), 837
<code>wait()</code> ( <code>pylablib.devices.Tektronix.base.DPO2000</code> method), 901	<code>wait_dev()</code> ( <code>pylablib.devices.Sirah.Matisse.SirahMatisse</code> method), 863
<code>wait()</code> ( <code>pylablib.devices.Tektronix.base.ITektronixScope</code> method), 887	<code>wait_dev()</code> ( <code>pylablib.devices.Tektronix.base.DPO2000</code> method), 901
<code>wait()</code> ( <code>pylablib.devices.Tektronix.base.TDS2000</code> method), 894	<code>wait_dev()</code> ( <code>pylablib.devices.Tektronix.base.ITektronixScope</code> method), 887
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.misc.GenericPM</code> method), 949	<code>wait_dev()</code> ( <code>pylablib.devices.Tektronix.base.TDS2000</code> method), 894
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.misc.PM160</code> method), 953	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.misc.GenericPM</code> method), 949
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.serial.FW</code> method), 960	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.misc.PM160</code> method), 953
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.serial.FWv1</code> method), 963	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.serial.FW</code> method), 960
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.serial.MDT69xA</code> method), 967	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.serial.FWv1</code> method), 963
<code>wait()</code> ( <code>pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface</code> method), 956	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.serial.MDT69xA</code> method), 967
<code>wait()</code> ( <code>pylablib.devices.Voltcraft.multimeter.VC7055</code> method), 983	<code>wait_dev()</code> ( <code>pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface</code> method), 956
<code>wait_dev()</code> ( <code>pylablib.core.devio.SCPI.SCPIDevice</code> method), 167	<code>wait_dev()</code> ( <code>pylablib.devices.Voltcraft.multimeter.VC7055</code> method), 983
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.generic.GenericAWG</code> method), 461	<code>wait_done()</code> ( <code>pylablib.devices.interface.camera.FrameCounter</code> method), 994
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.Agilent33220Await_for_any_message()</code> method), 473	<code>wait_for_any_message()</code> ( <code>pylablib.core.thread.controller.QTaskThread</code> method), 363
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.Agilent33500</code> method), 467	<code>wait_for_any_message()</code> ( <code>pylablib.core.thread.controller.QThreadController</code> method), 343
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2000</code> method), 485	<code>wait_for_fine_tuning()</code> ( <code>pylablib.devices.M2.emm.EMM</code> method), 698
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.InstekAFG2225</code> method), 479	<code>wait_for_fine_tuning()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 702
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.RigolDG1000</code> method), 504	<code>wait_for_frame()</code> ( <code>pylablib.devices.M2.solstis.Solstis</code> method), 702
<code>wait_dev()</code> ( <code>pylablib.devices.AWG.specific.RSInstekAFG21000</code> method), 492	



<code>wait_for_frame()</code>	<code>lablib.devices.AlliedVision.Bonito.BonitoIMACamera</code> <code>method</code> ), 521	<code>wait_for_frame()</code>	<code>lablib.devices.Mightex.MightexSSeries.MightexSSeriesCamera</code> <code>method</code> ), 713
<code>wait_for_frame()</code>	<code>lablib.devices.AlliedVision.Bonito.IBonitoCamera</code> <code>method</code> ), 513	<code>wait_for_frame()</code>	<code>lablib.devices.PCO.SC2.PCOSC2Camera</code> <code>method</code> ), 762
<code>wait_for_frame()</code>	<code>lablib.devices.Andor.AndorSDK2.AndorSDK2Camera</code> <code>method</code> ), 533	<code>wait_for_frame()</code>	<code>lablib.devices.Photometrics.pvcam.PvcamCamera</code> <code>method</code> ), 778
<code>wait_for_frame()</code>	<code>lablib.devices.Andor.AndorSDK3.AndorSDK3Camera</code> <code>method</code> ), 543	<code>wait_for_frame()</code>	<code>lablib.devices.PhotonFocus.PhotonFocus.IPhotonFocusCamera</code> <code>method</code> ), 788
<code>wait_for_frame()</code>	<code>lablib.devices.Basler.pylon.BaslerPylonCamera</code> <code>method</code> ), 584	<code>wait_for_frame()</code>	<code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusBitFlowCa</code> <code>method</code> ), 812
<code>wait_for_frame()</code>	<code>lablib.devices.BitFlow.BitFlow.BitFlowCamera</code> <code>method</code> ), 596	<code>wait_for_frame()</code>	<code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusIMACam</code> <code>method</code> ), 796
<code>wait_for_frame()</code>	<code>lablib.devices.BitFlow.BitFlow.BitFlowFrameGrabber</code> <code>method</code> ), 590	<code>wait_for_frame()</code>	<code>lablib.devices.PhotonFocus.PhotonFocus.PhotonFocusSiSoCame</code> <code>method</code> ), 805
<code>wait_for_frame()</code>	<code>lablib.devices.DCAM.DCAM.DCAMCamera</code> <code>method</code> ), 621	<code>wait_for_frame()</code>	<code>lablib.devices.PrincetonInstruments.picam.PicamCamera</code> <code>method</code> ), 833
<code>wait_for_frame()</code>	<code>lablib.devices.IMAQ.IMAQ.IMAQCamera</code> <code>method</code> ), 648	<code>wait_for_frame()</code>	<code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareCamera</code> <code>method</code> ), 854
<code>wait_for_frame()</code>	<code>lablib.devices.IMAQ.IMAQ.IMAQFrameGrabber</code> <code>method</code> ), 641	<code>wait_for_frame()</code>	<code>lablib.devices.SiliconSoftware.fgrab.SiliconSoftwareFrameGrabb</code> <code>method</code> ), 847
<code>wait_for_frame()</code>	<code>lablib.devices.IMAQdx.IMAQdx.EthernetIMAQdxCamera</code> <code>method</code> ), 662	<code>wait_for_frame()</code>	<code>lablib.devices.Thorlabs.TLCAmra.ThorlabsTLCAmra</code> <code>method</code> ), 910
<code>wait_for_frame()</code>	<code>lablib.devices.IMAQdx.IMAQdx.IMAQdxCamera</code> <code>method</code> ), 656	<code>wait_for_frame()</code>	<code>lablib.devices.Thorlabs.TLCAmra.ThorlabsTLCAmra.RingBuffe</code> <code>method</code> ), 905
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.IAttributeCamera</code> <code>method</code> ), 1000	<code>wait_for_frame()</code>	<code>lablib.devices.uc480.uc480.UC480Camera</code> <code>method</code> ), 1031
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.IBinROICamera</code> <code>method</code> ), 1019	<code>wait_for_grabbing()</code>	<code>lablib.devices.Tektronix.base.DPO2000</code> <code>method</code> ), 901
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.ICamera</code> <code>method</code> ), 991	<code>wait_for_grabbing()</code>	<code>lablib.devices.Tektronix.base.ITektronixScope</code> <code>method</code> ), 881
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.IExposureCamera</code> <code>method</code> ), 1010	<code>wait_for_grabbing()</code>	<code>lablib.devices.Tektronix.base.TDS2000</code> <code>method</code> ), 894
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.IGrabberAttributeCamera</code> <code>method</code> ), 1005	<code>wait_for_home()</code>	<code>lablib.devices.Thorlabs.kinesis.KinesisMotor</code> <code>method</code> ), 929
<code>wait_for_frame()</code>	<code>lablib.devices.interface.camera.IROICamera</code> <code>method</code> ), 1014	<code>wait_for_keypress()</code>	<code>(in module py-</code> <code>lablib.core.utils.general</code> ), 433
<code>wait_for_frame()</code>		<code>wait_for_measurement()</code>	<code>(py-</code> <code>lablib.devices.Cryomagnetics.base.LM500</code>

- method*), 605
- `wait_for_measurement()` (*pylablib.devices.Cryomagnetics.base.LM510 method*), 612
- `wait_for_message()` (*pylablib.core.thread.controller.QTaskThread method*), 363
- `wait_for_message()` (*pylablib.core.thread.controller.QThreadController method*), 343
- `wait_for_report()` (*pylablib.devices.M2.base.ICEBlocDevice method*), 697
- `wait_for_report()` (*pylablib.devices.M2.emm.EMM method*), 701
- `wait_for_report()` (*pylablib.devices.M2.solstis.Solstis method*), 707
- `wait_for_sample()` (*pylablib.devices.NI.daq.NIDAQ method*), 721
- `wait_for_scan()` (*pylablib.devices.Newport.picomotor.Picomotor8742 method*), 737
- `wait_for_status()` (*pylablib.devices.SmarAct.scu3d.SCU3D method*), 875
- `wait_for_status()` (*pylablib.devices.Thorlabs.kinesis.KinesisMotor method*), 929
- `wait_for_status()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method*), 935
- `wait_for_status()` (*pylablib.devices.Thorlabs.kinesis.MFF method*), 924
- `wait_for_stop()` (*pylablib.devices.Thorlabs.kinesis.KinesisMotor method*), 930
- `wait_for_sync()` (*pylablib.core.thread.controller.QTaskThread method*), 363
- `wait_for_sync()` (*pylablib.core.thread.controller.QThreadController method*), 343
- `wait_for_terascan_update()` (*pylablib.devices.M2.emm.EMM method*), 699
- `wait_for_terascan_update()` (*pylablib.devices.M2.solstis.Solstis method*), 704
- `wait_move()` (*pylablib.devices.Arcus.performax.Performax2110 method*), 560
- `wait_move()` (*pylablib.devices.Arcus.performax.Performax4110 method*), 554
- `wait_move()` (*pylablib.devices.Arcus.performax.Performax14110 method*), 561
- `wait_move()` (*pylablib.devices.Attocube.anc300.ANC300 method*), 568
- `wait_move()` (*pylablib.devices.Attocube.anc350.ANC350 method*), 572
- `wait_move()` (*pylablib.devices.Newport.picomotor.Picomotor8742 method*), 738
- `wait_move()` (*pylablib.devices.SmarAct.MCS2.MCS2 method*), 870
- `wait_move()` (*pylablib.devices.SmarAct.scu3d.SCU3D method*), 875
- `wait_move()` (*pylablib.devices.Standa.base.Standa8SMC method*), 878
- `wait_move()` (*pylablib.devices.Thorlabs.kinesis.KinesisMotor method*), 930
- `wait_move()` (*pylablib.devices.Thorlabs.kinesis.KinesisPiezoMotor method*), 935
- `wait_move()` (*pylablib.devices.Trinamic.base.TMCM1110 method*), 975
- `wait_move()` (*pylablib.devices.Trinamic.base.TMCMx110 method*), 980
- `wait_scan()` (*pylablib.devices.Sirah.Matisse.SirahMatisse method*), 860
- `wait_start()` (*pylablib.devices.interface.camera.FrameCounter method*), 994
- `wait_sync()` (*pylablib.core.devio.SCPi.SCPIDevice method*), 167
- `wait_sync()` (*pylablib.devices.AWG.generic.GenericAWG method*), 461
- `wait_sync()` (*pylablib.devices.AWG.specific.Agilent33220A method*), 473
- `wait_sync()` (*pylablib.devices.AWG.specific.Agilent33500 method*), 467
- `wait_sync()` (*pylablib.devices.AWG.specific.InstekAFG2000 method*), 485
- `wait_sync()` (*pylablib.devices.AWG.specific.InstekAFG2225 method*), 479
- `wait_sync()` (*pylablib.devices.AWG.specific.RigolDG1000 method*), 504
- `wait_sync()` (*pylablib.devices.AWG.specific.RSInstekAFG21000 method*), 492
- `wait_sync()` (*pylablib.devices.AWG.specific.TektronixAFG1000 method*), 498
- `wait_sync()` (*pylablib.devices.Cryocon.base.Cryocon1x method*), 603
- `wait_sync()` (*pylablib.devices.Cryomagnetics.base.LM500 method*), 608
- `wait_sync()` (*pylablib.devices.Cryomagnetics.base.LM510 method*), 612
- `wait_sync()` (*pylablib.devices.Keithley.multimeter.Keithley2110 method*), 670
- `wait_sync()` (*pylablib.devices.Lakeshore.base.Lakeshore218 method*), 676
- `wait_sync()` (*pylablib.devices.Lakeshore.base.Lakeshore370 method*), 676

method), 681

wait\_sync() (pylablib.devices.PhysikInstrumente.base.PIE515 method), 823

wait\_sync() (pylablib.devices.Rigol.power\_supply.DP1116A method), 837

wait\_sync() (pylablib.devices.Sirah.Matisse.SirahMatisse method), 863

wait\_sync() (pylablib.devices.Tektronix.base.DPO2000 method), 901

wait\_sync() (pylablib.devices.Tektronix.base.ITektronixScope method), 887

wait\_sync() (pylablib.devices.Tektronix.base.TDS2000 method), 894

wait\_sync() (pylablib.devices.Thorlabs.misc.GenericPM method), 949

wait\_sync() (pylablib.devices.Thorlabs.misc.PM160 method), 953

wait\_sync() (pylablib.devices.Thorlabs.serial.FW method), 960

wait\_sync() (pylablib.devices.Thorlabs.serial.FWv1 method), 964

wait\_sync() (pylablib.devices.Thorlabs.serial.MDT69xA method), 967

wait\_sync() (pylablib.devices.Thorlabs.serial.ThorlabsSerial method), 957

wait\_sync() (pylablib.devices.Voltcraft.multimeter.VC7055 method), 984

wait\_until() (pylablib.core.thread.controller.QTaskThread method), 363

wait\_until() (pylablib.core.thread.controller.QThreadController method), 343

wait\_until() (pylablib.core.thread.synchronizing.QMultiThreadNotifier method), 368

waiting() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 331

waiting() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 331

waiting() (pylablib.core.thread.notifier.ISkippableNotifier method), 366

waiting() (pylablib.core.thread.synchronizing.QThreadNotifier method), 368

waiting\_state() (pylablib.core.thread.callsync.QCallResultSynchronizer method), 331

waiting\_state() (pylablib.core.thread.callsync.QDirectResultSynchronizer method), 332

waiting\_state() (pylablib.core.thread.notifier.ISkippableNotifier method), 366

waiting\_state() (pylablib.core.thread.synchronizing.QThreadNotifier method), 368

walk\_dir() (in module pylablib.core.utils.files), 415

warnings (pylablib.devices.PCO.SC2.TCameraStatus attribute), 755

wheelEvent() (pylablib.core.gui.widgets.combo\_box.ComboBox method), 234

widget (pylablib.core.gui.widgets.container.TChild attribute), 236

widget (pylablib.core.gui.widgets.param\_table.ParamTable.ParamRow attribute), 285

width (pylablib.core.dataproc.feature.Baseline attribute), 135

width (pylablib.core.dataproc.feature.Peak attribute), 135

width (pylablib.devices.interface.camera.TFrameSize attribute), 989

width (pylablib.devices.Thorlabs.kinesis.TKCubeTrigPosParams attribute), 920

window (pylablib.devices.Lakeshore.base.TLakeshore218FilterSettings attribute), 672

window (pylablib.devices.Lakeshore.base.TLakeshore370FilterSettings attribute), 677

with\_traceback() (pylablib.core.devio.base.DeviceError method), 170

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceBackendError method), 170

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceFT232Error method), 178

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceHIDError method), 186

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceNetworkError method), 181

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceRecordedError method), 189

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceSerialError method), 175

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceUSBError method), 183

with\_traceback() (pylablib.core.devio.comm\_backend.DeviceVisaError method), 172

with\_traceback() (pylablib.core.devio.hid\_base.HIDError method), 196

with\_traceback() (pylablib.core.devio.hid\_base.HIDLibError method), 196

with\_traceback() (pylablib.core.devio.hid\_base.HIDLibError method), 196

with\_traceback() (pylablib.core.devio.hid\_base.HIDLibError method), 196

	<i>lablib.core.devio.hid_base.HIDTimeoutError</i>	<i>method</i> ), 550
	<i>method</i> ), 196	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.core.gui.limiter.LimitError</i>	<i>lablib.devices.Andor.base.AndorNotSupportedError</i>
	<i>method</i> ), 308	<i>method</i> ), 550
<i>with_traceback()</i>	(py- <i>lablib.core.gui.value_handling.MissingGUIHandlerError</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 326	<i>lablib.devices.Andor.base.AndorTimeoutError</i>
<i>with_traceback()</i>	(py- <i>lablib.core.gui.value_handling.NoParameterError</i>	<i>method</i> ), 550
	<i>method</i> ), 311	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.DuplicateControllerThreadError</i>	<i>lablib.devices.Arcus.base.ArcusBackendError</i>
	<i>method</i> ), 369	<i>method</i> ), 551
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.InterruptException</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 370	<i>lablib.devices.Arcus.base.ArcusError</i> <i>method</i> ),
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.InterruptExceptionStop</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 370	<i>lablib.devices.Arduino.base.ArduinoBackendError</i>
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.NoControllerThreadError</i>	<i>method</i> ), 564
	<i>method</i> ), 369	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.NoMessageThreadError</i>	<i>lablib.devices.Arduino.base.ArduinoError</i>
	<i>method</i> ), 370	<i>method</i> ), 563
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.SkippedCallError</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 370	<i>lablib.devices.Attocube.base.AttocubeBackendError</i>
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.ThreadError</i>	<i>method</i> ), 574
	<i>method</i> ), 369	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.TimeoutThreadError</i>	<i>lablib.devices.Attocube.base.AttocubeError</i>
	<i>method</i> ), 369	<i>method</i> ), 574
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.SocketError</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 440	<i>lablib.devices.AWG.generic.GenericAWGBackendError</i>
<i>with_traceback()</i>	(py- <i>lablib.core.thread.threadprop.SocketTimeout</i>	<i>method</i> ), 455
	<i>method</i> ), 440	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.devices.Agilent.base.AgilentBackendError</i>	<i>lablib.devices.AWG.generic.GenericAWGError</i>
	<i>method</i> ), 505	<i>method</i> ), 455
<i>with_traceback()</i>	(py- <i>lablib.devices.Agilent.base.AgilentError</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 505	<i>lablib.devices.BitFlow.BitFlow.BitFlowError</i>
<i>with_traceback()</i>	(py- <i>lablib.devices.AlliedVision.Bonito.BonitoError</i>	<i>method</i> ), 584
	<i>method</i> ), 507	<i>with_traceback()</i> (py-
<i>with_traceback()</i>	(py- <i>lablib.devices.Andor.base.AndorError</i>	<i>lablib.devices.BitFlow.BitFlow.BitFlowTimeoutError</i>
	<i>method</i> ), 549	<i>method</i> ), 585
<i>with_traceback()</i>	(py- <i>lablib.devices.Andor.base.AndorFrameTransferError</i>	<i>with_traceback()</i> (py-
	<i>method</i> ), 549	<i>lablib.devices.Conrad.base.ConradBackendError</i>
		<i>method</i> ), 597
		<i>with_traceback()</i> (py-
		<i>lablib.devices.Conrad.base.ConradError</i>
		<i>method</i> ), 597
		<i>with_traceback()</i> (py-
		<i>lablib.devices.Cryocon.base.CryoconBackendError</i>
		<i>method</i> ), 600
		<i>with_traceback()</i> (py-
		<i>lablib.devices.Cryocon.base.CryoconError</i>
		<i>method</i> ), 599
		<i>with_traceback()</i> (py-
		<i>lablib.devices.Cryomagnetics.base.CryomagneticsBackendError</i>
		<i>method</i> ), 604
		<i>with_traceback()</i> (py-
		<i>lablib.devices.Cryomagnetics.base.CryomagneticsError</i>





<code>lablib.devices.PhysikInstrumente.base.PhysikInstrumenteBackendError</code> (method), 814	<code>lablib.devices.Trinamic.base.TrinamicError</code> (method), 971
<code>with_traceback()</code> (py- <code>lablib.devices.PhysikInstrumente.base.PhysikInstrumenteError</code> (method), 814	<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicTimeoutError</code> (method), 971
<code>with_traceback()</code> (py- <code>lablib.devices.Rigol.base.GenericRigolBackendError</code> (method), 834	<code>with_traceback()</code> (py- <code>lablib.devices.Voltcraft.base.GenericVoltcraftBackendError</code> (method), 980
<code>with_traceback()</code> (py- <code>lablib.devices.Rigol.base.GenericRigolError</code> (method), 834	<code>with_traceback()</code> (py- <code>lablib.devices.Voltcraft.base.GenericVoltcraftError</code> (method), 980
<code>with_traceback()</code> (py- <code>lablib.devices.Sirah.base.GenericSirahBackendError</code> (method), 864	<code>with_traceback()</code> (py- <code>lablib.devices.Voltcraft.multimeter.VC880ParseError</code> (method), 984
<code>with_traceback()</code> (py- <code>lablib.devices.Sirah.base.GenericSirahError</code> (method), 864	<code>WLM</code> (class in <code>pylablib.devices.HighFinesse.wlm</code> ), 626
<code>with_traceback()</code> (py- <code>lablib.devices.Sirah.tuner.FrequencyReadSirahError</code> (method), 864	<code>wrap()</code> (in module <code>pylablib.core.dataproc.table_wrap</code> ), 161
<code>with_traceback()</code> (py- <code>lablib.devices.SmarAct.base.SmarActError</code> (method), 873	<code>wrap1d()</code> (in module <code>py-</code> <code>lablib.core.dataproc.table_wrap</code> ), 161
<code>with_traceback()</code> (py- <code>lablib.devices.Standa.base.StandaBackendError</code> (method), 876	<code>wrap2d()</code> (in module <code>py-</code> <code>lablib.core.dataproc.table_wrap</code> ), 161
<code>with_traceback()</code> (py- <code>lablib.devices.Standa.base.StandaError</code> (method), 876	<code>wrap_annotated()</code> (py- <code>lablib.core.utils.ctypes_wrap.CFunctionWrapper</code> (method), 373
<code>with_traceback()</code> (py- <code>lablib.devices.Tektronix.base.TektronixBackendError</code> (method), 881	<code>wrap_base()</code> ( <code>pylablib.core.utils.ctypes_wrap.CFunctionWrapper</code> (method), 373
<code>with_traceback()</code> (py- <code>lablib.devices.Tektronix.base.TektronixError</code> (method), 880	<code>wrap_function()</code> (py- <code>lablib.core.utils.functions.FunctionSignature</code> (method), 421
<code>with_traceback()</code> (py- <code>lablib.devices.Thorlabs.base.ThorlabsBackendError</code> (method), 911	<code>writable</code> ( <code>pylablib.devices.Andor.AndorSDK3.AndorSDK3Attribute</code> attribute), 535
<code>with_traceback()</code> (py- <code>lablib.devices.Thorlabs.base.ThorlabsError</code> (method), 911	<code>writable</code> ( <code>pylablib.devices.Basler.pylon.BaslerPylonAttribute</code> attribute), 576
<code>with_traceback()</code> (py- <code>lablib.devices.Thorlabs.base.ThorlabsTimeoutError</code> (method), 911	<code>writable</code> ( <code>pylablib.devices.DCAM.DCAM.DCAMAttribute</code> attribute), 614
<code>with_traceback()</code> (py- <code>lablib.devices.Toptica.base.TopticaBackendError</code> (method), 968	<code>writable</code> ( <code>pylablib.devices.IMAQdx.IMAQdx.IMAQdxAttribute</code> attribute), 649
<code>with_traceback()</code> (py- <code>lablib.devices.Toptica.base.TopticaError</code> (method), 968	<code>writable</code> ( <code>pylablib.devices.Photometrics.pvcam.PvcamAttribute</code> attribute), 770
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicBackendError</code> (method), 971	<code>writable</code> ( <code>pylablib.devices.PhotonFocus.PhotonFocus.PFCamAttribute</code> attribute), 780
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicError</code> (method), 971	<code>writable</code> ( <code>pylablib.devices.PrincetonInstruments.picam.PicamAttribute</code> attribute), 825
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicTimeoutError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.FT232DeviceBackend</code> (method), 179
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicBackendError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.HIDeviceBackend</code> (method), 188
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.IDeviceCommBackend</code> (method), 172
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicTimeoutError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.NetworkDeviceBackend</code> (method), 182
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicBackendError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.PyUSBDeviceBackend</code> (method), 185
<code>with_traceback()</code> (py- <code>lablib.devices.Trinamic.base.TrinamicError</code> (method), 971	<code>write()</code> ( <code>pylablib.core.devio.comm_backend.RecordedDeviceBackend</code> (method), 185

[method](#)), 190  
[write\(\)](#) ([pylablib.core.devio.comm\\_backend.SerialDeviceBackend](#) [method](#)), 177  
[write\(\)](#) ([pylablib.core.devio.comm\\_backend.VisaDeviceBackend](#) [method](#)), 174  
[write\(\)](#) ([pylablib.core.devio.hid.HIDDevice](#) [method](#)), 195  
[write\(\)](#) ([pylablib.core.devio.SCPI.SCPIDevice](#) [method](#)), 167  
[write\(\)](#) ([pylablib.core.fileio.savefile.CSVTableOutputFileFormat](#) [method](#)), 226  
[write\(\)](#) ([pylablib.core.fileio.savefile.DictionaryOutputFileFormat](#) [method](#)), 227  
[write\(\)](#) ([pylablib.core.fileio.savefile.IBinaryOutputFileFormat](#) [method](#)), 227  
[write\(\)](#) ([pylablib.core.fileio.savefile.IOutputFileFormat](#) [method](#)), 224  
[write\(\)](#) ([pylablib.core.fileio.savefile.ITextOutputFileFormat](#) [method](#)), 225  
[write\(\)](#) ([pylablib.core.fileio.savefile.TableBinaryOutputFileFormat](#) [method](#)), 228  
[write\(\)](#) ([pylablib.core.utils.general.StreamFileLogger](#) [method](#)), 432  
[write\(\)](#) ([pylablib.devices.AWG.generic.GenericAWG](#) [method](#)), 461  
[write\(\)](#) ([pylablib.devices.AWG.specific.Agilent33220A](#) [method](#)), 473  
[write\(\)](#) ([pylablib.devices.AWG.specific.Agilent33500](#) [method](#)), 467  
[write\(\)](#) ([pylablib.devices.AWG.specific.InstekAFG2000](#) [method](#)), 486  
[write\(\)](#) ([pylablib.devices.AWG.specific.InstekAFG2225](#) [method](#)), 479  
[write\(\)](#) ([pylablib.devices.AWG.specific.RigolDG1000](#) [method](#)), 504  
[write\(\)](#) ([pylablib.devices.AWG.specific.RSInstekAFG21000](#) [method](#)), 492  
[write\(\)](#) ([pylablib.devices.AWG.specific.TektronixAFG1000](#) [method](#)), 498  
[write\(\)](#) ([pylablib.devices.Cryocon.base.Cryocon1x](#) [method](#)), 603  
[write\(\)](#) ([pylablib.devices.Cryomagnetics.base.LM500](#) [method](#)), 608  
[write\(\)](#) ([pylablib.devices.Cryomagnetics.base.LM510](#) [method](#)), 612  
[write\(\)](#) ([pylablib.devices.Keithley.multimeter.Keithley2110](#) [method](#)), 670  
[write\(\)](#) ([pylablib.devices.Lakeshore.base.Lakeshore218](#) [method](#)), 676  
[write\(\)](#) ([pylablib.devices.Lakeshore.base.Lakeshore370](#) [method](#)), 681  
[write\(\)](#) ([pylablib.devices.PhysikInstrumente.base.PIE515](#) [method](#)), 823  
[write\(\)](#) ([pylablib.devices.Rigol.power\\_supply.DP1116A](#) [method](#)), 837  
[write\(\)](#) ([pylablib.devices.Sirah.Matisse.SirahMatisse](#) [method](#)), 863  
[write\(\)](#) ([pylablib.devices.Tektronix.base.DPO2000](#) [method](#)), 901  
[write\(\)](#) ([pylablib.devices.Tektronix.base.ITektronixScope](#) [method](#)), 887  
[write\(\)](#) ([pylablib.devices.Tektronix.base.TDS2000](#) [method](#)), 894  
[write\(\)](#) ([pylablib.devices.Thorlabs.misc.GenericPM](#) [method](#)), 949  
[write\(\)](#) ([pylablib.devices.Thorlabs.misc.PM160](#) [method](#)), 953  
[write\(\)](#) ([pylablib.devices.Thorlabs.serial.FW](#) [method](#)), 960  
[write\(\)](#) ([pylablib.devices.Thorlabs.serial.FWv1](#) [method](#)), 964  
[write\(\)](#) ([pylablib.devices.Thorlabs.serial.MDT69xA](#) [method](#)), 967  
[write\(\)](#) ([pylablib.devices.Thorlabs.serial.ThorlabsSerialInterface](#) [method](#)), 957  
[write\(\)](#) ([pylablib.devices.Voltcraft.multimeter.VC7055](#) [method](#)), 984  
[write\\_comments\(\)](#) ([pylablib.core.fileio.savefile.CSVTableOutputFileFormat](#) [method](#)), 226  
[write\\_comments\(\)](#) ([pylablib.core.fileio.savefile.DictionaryOutputFileFormat](#) [method](#)), 227  
[write\\_comments\(\)](#) ([pylablib.core.fileio.savefile.ITextOutputFileFormat](#) [method](#)), 225  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.CSVTableOutputFileFormat](#) [method](#)), 226  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.DictionaryOutputFileFormat](#) [method](#)), 227  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.IBinaryOutputFileFormat](#) [method](#)), 227  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.IOutputFileFormat](#) [method](#)), 224  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.ITextOutputFileFormat](#) [method](#)), 225  
[write\\_data\(\)](#) ([pylablib.core.fileio.savefile.TableBinaryOutputFileFormat](#) [method](#)), 228  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.CSVTableOutputFileFormat](#) [method](#)), 226  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.DictionaryOutputFileFormat](#) [method](#)), 227  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.IBinaryOutputFileFormat](#) [method](#)), 227  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.IOutputFileFormat](#) [method](#)), 224  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.ITextOutputFileFormat](#) [method](#)), 225  
[write\\_file\(\)](#) ([pylablib.core.fileio.savefile.TableBinaryOutputFileFormat](#) [method](#)), 225

*method*), 228

`write_header()` (*pylablib.core.utils.general.StreamFileLogger*  
*method*), 431

`write_line()` (*pylablib.core.fileio.savefile.CSVTableOutputFileFormat*  
*static method*), 226

`write_line()` (*pylablib.core.fileio.savefile.DictionaryOutputFileFormat*  
*static method*), 227

`write_line()` (*pylablib.core.fileio.savefile.ITextOutputFileFormat*  
*static method*), 225

`write_multiple_rows()` (*pylablib.core.fileio.table\_stream.TableStreamFile*  
*method*), 231

`write_props()` (*pylablib.core.fileio.savefile.CSVTableOutputFileFormat*  
*method*), 226

`write_props()` (*pylablib.core.fileio.savefile.DictionaryOutputFileFormat*  
*method*), 227

`write_props()` (*pylablib.core.fileio.savefile.ITextOutputFileFormat*  
*method*), 225

`write_row()` (*pylablib.core.fileio.table\_stream.TableStreamFile*  
*method*), 231

`write_savetime()` (*pylablib.core.fileio.savefile.CSVTableOutputFileFormat*  
*method*), 226

`write_savetime()` (*pylablib.core.fileio.savefile.DictionaryOutputFileFormat*  
*method*), 227

`write_savetime()` (*pylablib.core.fileio.savefile.ITextOutputFileFormat*  
*method*), 225

`write_text_lines()` (*pylablib.core.fileio.table\_stream.TableStreamFile*  
*method*), 231

`wrng` (*pylablib.devices.PrincetonInstruments.picam.TROIConstraints*  
*attribute*), 825

## Y

`ybins` (*pylablib.devices.PrincetonInstruments.picam.TROIConstraints*  
*attribute*), 825

`ydiff` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings*  
*attribute*), 942

`year` (*pylablib.devices.Thorlabs.elliptec.TDeviceInfo* *attribute*), 912

`year` (*pylablib.devices.uc480.uc480.TTimestamp* *attribute*), 1024

`ygain` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`ymax` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`ymin` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`ypos` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings*  
*attribute*), 942

`ypos` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorSetpoint*  
*attribute*), 942

`yrng` (*pylablib.devices.PrincetonInstruments.picam.TROIConstraints*  
*attribute*), 825

## Z

`zip_file()` (in module *pylablib.core.utils.files*), 418

`zip_folder()` (in module *pylablib.core.utils.files*), 418

`zip_multiple_files()` (in module *pylablib.core.utils.files*), 418

## X

`xbins` (*pylablib.devices.PrincetonInstruments.picam.TROIConstraints*  
*attribute*), 825

`xdiff` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings*  
*attribute*), 942

`xgain` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`XGS600` (class in *pylablib.devices.Agilent.pressure*), 505

`xmax` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`xmin` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorOutputParams*  
*attribute*), 942

`xpos` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorReadings*  
*attribute*), 942

`xpos` (*pylablib.devices.Thorlabs.kinesis.TQuadDetectorSetpoint*  
*attribute*), 942

`xrng` (*pylablib.devices.PrincetonInstruments.picam.TROIConstraints*  
*attribute*), 825

`xy2c()` (in module *pylablib.core.dataproc.utils*), 165