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# **RobotPy WPILib Documentation**

*Release master*

**RobotPy development team**

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Welcome to RobotPy! RobotPy is a community of FIRST mentors and students dedicated to developing python-related projects for the FIRST Robotics Competition.

This documentation site describes how to use the python version of WPILib. It is a pure python implementation of WPILib, so that teams can use to write their robot code in Python, a powerful dynamic programming language.

There is a lot of good documentation, but there's still room for improvement. We welcome contributions from others!





## 1.1 Getting Started

Welcome to RobotPy! RobotPy is a community of FIRST mentors and students dedicated to developing python-related projects for the FIRST Robotics Competition.

RobotPy WPILib is a set of libraries that are used on your roboRIO to enable you to use Python as your main programming language for FIRST Robotics robot development. It includes support for all components that are supported by WPILib's Java implementation. The following instructions tell you how to install RobotPy on your robot.

If you want to run your python code on your computer (of course you do!), then you need to install our python development support tools, which is a separate project of ours called pyfrc. For more information, check out the [pyfrc documentation site](#).

---

**Note:** Once you've got robotpy installed on your robot, check out *Anatomy of a robot* to learn how to write robot code using python and RobotPy.

---

### 1.1.1 Automated installation

RobotPy is truly cross platform, and can be installed from Windows, most Linux distributions, and from Mac OSX also. Here's how you do it:

- [Download RobotPy from github](#)
- [Make sure Python 3.4 is installed](#)

Unzip the RobotPy zipfile somewhere on your computer (not on the RoboRIO), and there should be an installer.py there. Open up a command line, change directory to the installer location, and run this:

```
Windows:  py installer.py install-robotpy
Linux/OSX: python3 installer.py install-robotpy
```

It will ask you a few questions, and copy the right files over to your robot and set things up for you.

Next, you'll want to create some code (or maybe use one of our examples), and upload it to your robot! Refer to our *Programmer's Guide* for more information.

### Upgrading

From the same directory that you unzipped previously, you can run the same installer script to upgrade your robotpy installation. You need to do it in two phases, one while connected to the internet to download the new release, and one while connected to the Robot's network.

When connected to the internet:

```
Windows: py installer.py download-robotpy
Linux/OSX: python3 installer.py download-robotpy
```

Then connect to the Robot's network:

```
Windows: py installer.py install-robotpy
Linux/OSX: python3 installer.py install-robotpy
```

If you want to use a beta version of RobotPy (if available, you can add the `-pre` argument to the download/install command listed above.

### 1.1.2 Manual installation

**Warning:** This isn't recommended, so you're on your own if you go this route.

If you really want to do this, it's not so bad, but then you lose out on the benefits of the automated installer – in particular, this method requires internet access to install the files on the RoboRIO in case you need to reimage your RoboRIO.

- Connect your RoboRIO to the internet
- SSH in, and copy the following to `/etc/opkg/robotpy.conf`:

```
src/gz robotpy http://www.tortall.net/~robotpy/feeds/2014
```

- Run this:

```
opkg install python3
```

- Then run this:

```
pip3 install pynivision robotpy-hal-roborio wpilib
```

**Note:** When powered off, your RoboRIO does not keep track of the correct date, and as a result pip may fail with an SSL related error message. To set the date, you can either:

- Set the date via the web interface
- You can login to your roboRIO via SSH, and set the date via the date command:

```
date -s "2015-01-03 00:00:00"
```

Upgrading requires you to run the same commands, but with the appropriate flags set to tell pip3/opkg to upgrade the packages for you.

## 1.2 Programmer's Guide

### 1.2.1 Anatomy of a robot

---

**Note:** The following assumes you have some familiarity with python, and is meant as a primer to creating robot code using the python version of wpilib. If you're not familiar with python, you might try these resources:

- [CodeAcademy](#)
  - [Wikibooks python tutorial](#)
  - [Python 3.4 Tutorial](#)
- 

This tutorial will go over the things necessary for very basic robot code that can run on an FRC robot using the python version of WPILib. Code that is written for RobotPy can be ran on your PC using various simulation tools that are available.

#### Create your Robot code

Your robot code must start within a file called *robot.py*. Your code can do anything a normal python program can, such as importing other python modules & packages. Here are the basic things you need to know to get your robot code working!

#### Importing necessary modules

All of the code that actually interacts with your robot's hardware is contained in a library called WPILib. This library was originally implemented in C++ and Java. Your robot code must import this library module, and create various objects that can be used to interface with the robot hardware.

To import wpilib, it's just as simple as this:

```
import wpilib
```

---

**Note:** Because RobotPy implements the same WPILib as C++/Java, you can learn a lot about how to write robot code from the many C++/Java focused WPILib resources that already exist, including FIRST's official documentation. Just translate the code into python.

---

#### Robot object

Every valid robot program must define a robot object that inherits from either *wpilib.IterativeRobot* or *wpilib.SampleRobot*. These objects define a number of functions that you need to override, which get called at various times.

- *wpilib.IterativeRobot* functions
  - *wpilib.SampleRobot* functions
- 

**Note:** It is recommended that inexperienced programmers use the IterativeRobot framework, which is what this guide will discuss.

---

An incomplete version of your robot object might look like this:

```
class MyRobot(wplib.IterativeRobot):  
  
    def robotInit(self):  
        self.motor = wpilib.Jaguar(1)
```

The `robotInit` function is where you initialize data that needs to be initialized when your robot first starts. Examples of this data includes:

- Variables that are used in multiple functions
- Creating various `wplib` objects for devices and sensors
- Creating instances of other objects for your robot

In python, the constructor for an object is the `__init__` function. Instead of defining a constructor for your main robot object, you can override `robotInit` instead. If you do decide that you want to override `__init__`, then you must call `super().__init__()` in your `__init__` method, or an exception will be thrown.

### Adding motors and sensors

Everything that interacts with the robot hardware directly must use the `wplib` library to do so. Starting in 2015, full documentation for the python version of WPILib is published online. Check out the API documentation ([wplib](#)) for details on all the objects available in WPILib.

---

**Note:** You should *only* create instances of your motors and other WPILib hardware devices (Gyros, Joysticks, Sensors, etc) either during or after `robotInit` is called on your main robot object. If you don't, there are a lot of things that will fail.

---

### Creating individual devices

Let's say you wanted to create an object that interacted with a Jaguar motor controller via PWM. First, you would read through the table ([wplib](#)) and see that there is a `Jaguar` object. Looking further, you can see that the constructor takes a single argument that indicates which PWM port to connect to. You could create the `Jaguar` object that is using port 4 using the following python code in your `robotInit` method:

```
self.motor = wpilib.Jaguar(4)
```

Looking through the documentation some more, you would notice that to set the PWM value of the motor, you need to call the `Jaguar.set()` function. The docs say that the value needs to be between -1.0 and 1.0, so to set the motor full speed forward you could do this:

```
self.motor.set(1)
```

Other motors and sensors have similar conventions.

### Robot drivetrain control

For standard types of drivetrains (2 or 4 wheel, and mecanum), you'll want to use the `RobotDrive` class to control the motors instead of writing your own code to do it. When you create a `RobotDrive` object, you either specify which PWM channels to automatically create a motor for:

```
self.robot_drive = wpilib.RobotDrive(0,1)
```

Or you can pass in motor controller instances:

```
l_motor = wpilib.Talon(0)
r_motor = wpilib.Talon(1)
self.robot_drive = wpilib.RobotDrive(l_motor, r_motor)
```

Once you have one of these objects, it has various methods that you can use to control the robot via joystick, or you can specify the control inputs manually.

#### See also:

Documentation for the `wpilib.RobotDrive` object, and the FIRST WPILib Programming Guide.

## Robot Operating Modes (IterativeRobot)

During a competition, the robot transitions into various modes depending on the state of the game. During each mode, functions on your robot class are called. The name of the function varies based on which mode the robot is in:

- `disabledXXX` - Called when robot is disabled
- `autonomousXXX` - Called when robot is in autonomous mode
- `teleopXXX` - Called when the robot is in teleoperated mode
- `testXXX` - Called when the robot is in test mode

Each mode has two functions associated with it. `xxxInit` is called when the robot first switches over to the mode, and `xxxPeriodic` is called 50 times a second (approximately – it’s actually called as packets are received from the driver station).

For example, a simple robot that just drives the robot using a single joystick might have a `teleopPeriodic` function that looks like this:

```
def teleopPeriodic(self):
    self.robot_drive.arcadeDrive(self.stick)
```

This function gets called over and over again (about 50 times per second) while the robot remains in teleoperated mode.

**Warning:** When using the `IterativeRobot` as your Robot class, you should avoid doing the following operations in the `xxxPeriodic` functions or functions that have `xxxPeriodic` in the call stack:

- Never use `Timer.delay()`, as you will momentarily lose control of your robot during the delay, and it will not be as responsive.
- Avoid using loops, as unexpected conditions may cause you to lose control of your robot.

## Main block

Languages such as Java require you to define a ‘static main’ function. In python, because every `.py` file is usable from other python programs, you need to [define a code block which checks for `\_\_main\_\_`](#). Inside your main block, you tell WPILib to launch your robot’s code using the following invocation:

```
if __name__ == '__main__':
    wpilib.run(MyRobot)
```

This simple invocation is sufficient for launching your robot code on the robot, and also provides access to various RobotPy-enabled extensions that may be available for testing your robot code, such as `pyfrc` and `robotpy-frcsim`.

## Putting it all together

If you combine all the pieces above, you end up with something like this below, taken from one of the samples in our github repository.

```
#!/usr/bin/env python3
"""
    This is a good foundation to build your robot code on
"""

import wpilib

class MyRobot(wpilib.IterativeRobot):

    def robotInit(self):
        """
            This function is called upon program startup and
            should be used for any initialization code.
        """
        self.robot_drive = wpilib.RobotDrive(0,1)
        self.stick = wpilib.Joystick(1)

    def autonomousInit(self):
        """This function is run once each time the robot enters autonomous mode."""
        self.auto_loop_counter = 0

    def autonomousPeriodic(self):
        """This function is called periodically during autonomous."""

        # Check if we've completed 100 loops (approximately 2 seconds)
        if self.auto_loop_counter < 100:
            self.robot_drive.drive(-0.5, 0) # Drive forwards at half speed
            self.auto_loop_counter += 1
        else:
            self.robot_drive.drive(0, 0) #Stop robot

    def teleopPeriodic(self):
        """This function is called periodically during operator control."""
        self.robot_drive.arcadeDrive(self.stick)

    def testPeriodic(self):
        """This function is called periodically during test mode."""
        wpilib.LiveWindow.run()

if __name__ == "__main__":
    wpilib.run(MyRobot)
```

There are a few different python-based robot samples available, and you can find them at [our github site](#).

## Next Steps

This is a good foundation for building your robot, next you will probably want to know about *Running Robot Code*.

### 1.2.2 Running Robot Code

Now that you've created your first Python robot program, you probably want to know how to run the code.

## On the robot (using pyfrc)

The easiest way to install code on the robot is to use pyfrc.

1. Make sure you have RobotPy installed on the robot
2. Make sure you have pyfrc installed (see the installation guide).
3. Once that is done, you can just run the following command and it will upload the code and start it immediately.

```
Windows:  py robot.py deploy
Linux/OSX: python3 robot.py deploy
```

Note that when you run this command like that, you won't get any feedback from the robot whether your code actually worked or not. If you want to see the feedback from your robot, a really useful option is `--nc`. This will cause the deploy command to show your program's console output, by launching a netconsole listener.

```
Windows:  py robot.py deploy --nc
Linux/OSX: python3 robot.py deploy --nc
```

You can watch your robot code's output (and see any problems) by using the netconsole program (you can either use NI's tool, or [pynetconsole](#)). You can use netconsole and the normal FRC tools to interact with the running robot code.

If you're having problems deploying code to the robot, check out the troubleshooting section at <http://pyfrc.readthedocs.org/en/latest/deploy.html>

## On the robot (manual)

If you don't have (or don't want) to install pyfrc, running code manually is pretty simple too.

1. Make sure you have RobotPy installed on the robot
2. Use scp or sftp (Filezilla is a great GUI product to use for this) to copy your robot code to the RoboRIO
3. ssh into the RoboRIO, and run your robot code manually

```
python3 robot.py run
```

Your driver station should be able to connect to your code, and it will be able to operate your robot!

---

**Note:** This is good for running experimental code, but it won't start the code when the robot starts up. Use pyfrc to do that.

---

## On your computer

Once installed, pyfrc provides a number of commands to interact with your robot code. For example, to launch the tk-based simulator, run the following command on your code:

```
Windows:  py robot.py sim
Linux/OSX: python3 robot.py sim
```

Check out the pyfrc documentation for [more usage details](#).

### Gazebo simulation

This is currently experimental, and will be updated in the coming weeks. If you want to play with it now (and help us fix the bugs!), check out the [robotpy-frcsim github repository](#).

### Next steps

The next section discusses a very important part of writing robot code – *Simulation and Testing*.

## 1.2.3 Simulation and Testing

An important (but often neglected) part of developing your robot code is to test it! Because we feel strongly about testing and simulation, the RobotPy project provides tools to make those types of things easier through the [pyfrc](#) project.

### Adding tests to your robot

pyfrc comes with builtin tests that you can add to your robot code that will test basic functionality of most robots. As of pyfrc 2016.1.1, you can add these tests to your robot by executing this:

```
Windows:  py robot.py add-tests
Linux/OSX: python3 robot.py add-tests
```

### Customized tests

For more detailed information, check out the [pyfrc documentation](#).

### Next Steps

Learn more about some *Best Practices* when creating robot code.

## 1.2.4 Best Practices

This section has a selection of things that other teams have found to be good things to keep in mind to build robot code that works consistently, and to eliminate possible failures.

### Contents

- *Best Practices*
  - *Make sure you're running the latest version of RobotPy!*
  - *Don't use the print statement/logger excessively*
  - *Don't die during the competition!*
- *Next Steps*

If you have things to add to this section, feel free to submit a pull request!



## Make sure you're running the latest version of RobotPy!

Seriously. We try to fix bugs as we find them, and if you haven't updated recently, check to see if you're out of date! This is particularly true this year.

## Don't use the print statement/logger excessively

Printing output can easily take up a large proportion of your robot code CPU usage if you do it often enough. Try to limit the amount of things that you print, and your robot will perform better.

Instead, you may want to use this pattern to only print once every half second (or whatever arbitrary period):

```
# Put this in robotInit
self.printTimer = wpilib.Timer()
self.printTimer.start()

..

# Put this where you want to print
if self.printTimer.hasPeriodPassed(0.5):
    self.logger.info("Something happened")
```

Remember, during a competition you can't actually see the output of Netconsole (it gets blocked by the field network), so there's not much point in using these except for diagnostics off the field. In a competition, disable it.

## Don't die during the competition!

If you've done any amount of programming in python, you'll notice that it's really easy to crash your robot code – all you need to do is mistype something and BOOM you're done. When python encounters errors (or components such as WPILib or HAL), then what happens is an exception is raised.

---

**Note:** If you don't know what exceptions are and how to deal with them, you should read [this](#)

---

There's a lot of things that can cause your program to crash, and generally the best way to make sure that it doesn't crash is **test your code**. RobotPy provides some great tools to allow you to simulate your code, and to write unit tests that make sure your code actually works. Whenever you deploy your code using pyfrc, it tries to run your robot code's tests – and this is to try and prevent you from uploading code that will fail on the robot.

However, invariably even with all of the testing you do, something will go wrong during that really critical match, and your code will crash. No fun. Luckily, there's a good technique you can use to help prevent that!

What you need to do is set up a generic exception handler that will catch exceptions, and then if you detect that the FMS is attached (which is only true when you're in an actual match), just continue on instead of crashing the code.

---

**Note:** Most of the time when you write code, you never want to create generic exception handlers, but you should try to catch specific exceptions. However, this is a special case and we actually do want to catch all exceptions.

---

Here's what I mean:

```
try:
    # some code goes here
except:
    if not self.isFmsAttached():
        raise
```

What this does is run some code, and if an exception occurs in that code block, and the FMS is connected, then execution just continues and hopefully everything continues working. However (and this is important), if the FMS is not attached (like in a practice match), then the `raise` keyword tells python to raise the exception anyways, which will most likely crash your robot. But this is good in practice mode – if your driver station is attached, the error and a stack trace should show up in the driver station log, so you can debug the problem.

Now, a naive implementation would just put all of your code inside of a single exception handler – but that’s a bad idea. What we’re trying to do is make sure that failures in a single part of your robot don’t cause the rest of your robot code to not function. What we generally try to do is put each logical piece of code in the main robot loop (`teleopPeriodic`) in its own exception handler, so that failures are localized to specific subsystems of the robot.

With these thoughts in mind, here’s an example of what I mean:

```
def teleopPeriodic(self):

    try:
        if self.joystick.getTrigger():
            self.arm.raise_arm()
    except:
        if not self.isFmsAttached():
            raise

    try:
        if self.joystick.getRawButton(2):
            self.ball_intake.()
    except:
        if not self.isFmsAttached():
            raise

    # and so on...

    try:
        self.robot_drive.arcadeDrive(self.joystick)
    except:
        if not self.isFmsAttached():
            raise
```

---

**Note:** In particular, I always recommend making sure that the call to your robot’s drive function is in it’s own exception handler, so even if everything else in the robot dies, at least you can still drive around.

---

### 1.2.5 Next Steps

Next we’ll discuss some topic that will be decided upon in the future, if someone writes more documentation here. Until then, remember that the FIRST documentation and our example programs are great resources to learn more about programming with WPILib.

## 1.3 Hardware & Sensors

FIRST has put together a lot of great documentation that can tell you how to connect hardware devices and interact with it from robot code.

- [Using actuators \(motors, servos, and relays\)](#)
- [Using CAN Devices](#)

- WPILib Sensors
- Driver Station Inputs and Feedback

While their documentation code samples are in C++ and Java, it's fairly straightforward to translate them to python – RobotPy includes support for all components that are supported by WPILib's Java implementation, and generally the objects have the same name and method names.

If you have problems translating their code samples into Python, you can use our support resources to get help (see [Support](#)).

## 1.4 wpilib Package

The WPI Robotics library (WPILib) is a set of classes that interfaces to the hardware in the FRC control system and your robot. There are classes to handle sensors, motors, the driver station, and a number of other utility functions like timing and field management. The library is designed to:

- Deal with all the low level interfacing to these components so you can concentrate on solving this year's "robot problem". This is a philosophical decision to let you focus on the higher-level design of your robot rather than deal with the details of the processor and the operating system.
- Understand everything at all levels by making the full source code of the library available. You can study (and modify) the algorithms used by the gyro class for oversampling and integration of the input signal or just ask the class for the current robot heading. You can work at any level.

|   |  |
|---|--|
| <code>wpilib._impl.CameraServer()</code>          |  |
| <code>wpilib._impl.USBCamera([name])</code>       |  |
| <code>wpilib.ADXL345_I2C(port, range)</code>      | ADXL345 accelerometer device via i2c   |
| <code>wpilib.ADXL345_SPI(port, range)</code>      | ADXL345 accelerometer device via spi   |
| <code>wpilib.ADXL362(range[, port])</code>        | ADXL362 SPI Accelerometer.   |
| <code>wpilib.ADXRS450_Gyro([port])</code>         | Use a rate gyro to return the robots heading relative to a starting position.  |
| <code>wpilib.AnalogAccelerometer(channel)</code>  | Analog Accelerometer   |
| <code>wpilib.AnalogGyro(channel[, ...])</code>    | Interface to a gyro device via an <i>AnalogInput</i>                           |
| <code>wpilib.AnalogInput(channel)</code>          | Analog input   |
| <code>wpilib.AnalogOutput(channel)</code>         | Analog output  |
| <code>wpilib.AnalogPotentiometer(channel)</code>  | Reads a potentiometer via an <i>AnalogInput</i>                                |
| <code>wpilib.AnalogTrigger(channel)</code>        | Converts an analog signal into a digital signal                                |
| <code>wpilib.AnalogTriggerOutput(...)</code>      | Represents a specific output from an <i>AnalogTrigger</i>                      |
| <code>wpilib.BuiltInAccelerometer([range])</code> | Built-in accelerometer device  |
| <code>wpilib.CANJaguar(deviceNumber)</code>       | Texas Instruments Jaguar Speed Controller as a CAN device.                     |
| <code>wpilib.CANTalon(deviceNumber[, ...])</code> | Talon SRX device as a CAN device   |
| <code>wpilib.Compressor([pcmId])</code>           | Operates the PCM (Pneumatics compressor module)                                |
| <code>wpilib.ControllerPower</code>               | Provides access to power levels on the RoboRIO                                 |
| <code>wpilib.Counter(*args, **kwargs)</code>      | Counts the number of ticks on a <i>DigitalInput</i> channel.                   |
| <code>wpilib.DigitalGlitchFilter()</code>         | Class to enable glitch filtering on a set of digital inputs.                   |
| <code>wpilib.DigitalInput(channel)</code>         | Reads a digital input.   |
| <code>wpilib.DigitalOutput(channel)</code>        | Writes to a digital output   |
| <code>wpilib.DigitalSource(channel, ...)</code>   | DigitalSource Interface.   |
| <code>wpilib.DoubleSolenoid(*args, ...)</code>    | Controls 2 channels of high voltage Digital Output.                            |
| <code>wpilib.DriverStation()</code>               | Provide access to the network communication data to / from the Driver Station. |
| <code>wpilib.Encoder(*args, **kwargs)</code>      | Reads from quadrature encoders.  |
| <code>wpilib.Filter(source)</code>                | Superclass for filters   |
| <code>wpilib.GearTooth(channel[, ...])</code>     | Interface to the gear tooth sensor supplied by FIRST                           |

Table 1.1 – continued from previous page

|  |  |
|--|--|
| <code>wplib.GyroBase()</code>                          | GyroBase is the common base class for Gyro implementations such as <i>AnalogGyro</i>                         |
| <code>wplib.I2C(port, deviceAddress[, simPort])</code> | I2C bus interface class.   |
| <code>wplib.InterruptableSensorBase()</code>           | Base for sensors to be used with interrupts  |
| <code>wplib.IterativeRobot()</code>                    | IterativeRobot implements a specific type of Robot Program framework, extending <i>RobotBase</i>             |
| <code>wplib.Jaguar(channel)</code>                     | Texas Instruments / Vex Robotics Jaguar Speed Controller as a PWM device.                                    |
| <code>wplib.Joystick(port[, ...])</code>               | Handle input from standard Joysticks connected to the Driver Station.  |
| <code>wplib.LinearDigitalFilter(...)</code>            | This class implements a linear, digital filter.  |
| <code>wplib.LiveWindow</code>                          | The public interface for putting sensors and actuators on the LiveWindow.                                    |
| <code>wplib.LiveWindowSendable</code>                  | A special type of object that can be displayed on the live window.   |
| <code>wplib.MotorSafety()</code>                       | Provides mechanisms to safely shutdown motors if they aren't updated often enough                            |
| <code>wplib.PIDController(*args, ...)</code>           | Can be used to control devices via a PID Control Loop.   |
| <code>wplib.PowerDistributionPanel([...])</code>       | Use to obtain voltage, current, temperature, power, and energy from the CAN PD                               |
| <code>wplib.Preferences()</code>                       | Provides a relatively simple way to save important values to the RoboRIO to access later                     |
| <code>wplib.PWM(channel)</code>                        | Raw interface to PWM generation in the FPGA.   |
| <code>wplib.Relay(channel[, direction])</code>         | Controls VEX Robotics Spike style relay outputs.   |
| <code>wplib.Resource(size)</code>                      | Tracks resources in the program.   |
| <code>wplib.RobotBase()</code>                         | Implement a Robot Program framework.   |
| <code>wplib.RobotDrive(*args, **kwargs)</code>         | Operations on a robot drivetrain based on a definition of the motor configuration.                           |
| <code>wplib.RobotState</code>                          | Provides an interface to determine the current operating state of the robot code.                            |
| <code>wplib.SafePWM(channel)</code>                    | A raw PWM interface that implements the <i>MotorSafety</i> interface   |
| <code>wplib.SampleRobot()</code>                       | A simple robot base class that knows the standard FRC competition states (disabled, autonomous, teleop, etc) |
| <code>wplib.SD540(channel)</code>                      | Mindsensors SD540 Speed Controller   |
| <code>wplib.Sendable</code>                            | The base interface for objects that can be sent over the network   |
| <code>wplib.SendableChooser()</code>                   | A useful tool for presenting a selection of options to be displayed on the LiveWindow                        |
| <code>wplib.SensorBase</code>                          | Base class for all sensors   |
| <code>wplib.Servo(channel)</code>                      | Standard hobby style servo   |
| <code>wplib.SmartDashboard</code>                      | The bridge between robot programs and the SmartDashboard on the laptop                                       |
| <code>wplib.Solenoid(*args, **kwargs)</code>           | Solenoid class for running high voltage Digital Output.  |
| <code>wplib.SolenoidBase(moduleNumber)</code>          | SolenoidBase class is the common base class for the Solenoid and DoubleSolenoid                              |
| <code>wplib.Spark(channel)</code>                      | REV Robotics SPARK Speed Controller  |
| <code>wplib.SPI(port[, simPort])</code>                | Represents a SPI bus port  |
| <code>wplib.Talon(channel)</code>                      | Cross the Road Electronics (CTRE) Talon and Talon SR Speed Controller via PWM                                |
| <code>wplib.TalonSRX(channel)</code>                   | Cross the Road Electronics (CTRE) Talon SRX Speed Controller via PWM   |
| <code>wplib.Timer()</code>                             | Provides time-related functionality for the robot  |
| <code>wplib.Ultrasonic(pingChannel, ...)</code>        | Ultrasonic rangefinder control   |
| <code>wplib.Utility</code>                             | Contains global utility functions  |
| <code>wplib.Victor(channel)</code>                     | VEX Robotics Victor 888 Speed Controller via PWM   |
| <code>wplib.VictorSP(channel)</code>                   | VEX Robotics Victor SP Speed Controller via PWM  |

### 1.4.1 CameraServer

```
class wplib._impl.USBCamera (name=None)
```

```
    Bases: object
```

```
    class WhiteBalance
```

```
        Bases: object
```

```
        kFixedFlourescent2 = 5200
```

```
        kFixedFluorescent1 = 5100
```

```
        kFixedIndoor = 3000
```

```

kFixedOutdoor1 = 4000
kFixedOutdoor2 = 5000
USBCamera.closeCamera ()
USBCamera.getBrightness ()
    Get the brightness, as a percentage (0-100).
USBCamera.getImage (image)
USBCamera.getImageData (data, maxsize)
USBCamera.kDefaultCameraName = b'cam0'
USBCamera.openCamera ()
USBCamera.setBrightness (brightness)
    Set the brightness, as a percentage (0-100).
USBCamera.setExposureAuto ()
    Set the exposure to auto aperature.
USBCamera.setExposureHoldCurrent ()
    Set the exposure to hold current.
USBCamera.setExposureManual (value)
    Set the exposure to manual, as a percentage (0-100).
USBCamera.setFPS (fps)
USBCamera.setSize (width, height)
USBCamera.setWhiteBalanceAuto ()
    Set the white balance to auto.
USBCamera.setWhiteBalanceHoldCurrent ()
    Set the white balance to hold current.
USBCamera.setWhiteBalanceManual (value)
    Set the white balance to manual, with specified color temperature.
USBCamera.startCapture ()
USBCamera.stopCapture ()
USBCamera.updateSettings ()
class wpilib._impl.CameraServer
    Bases: object
static getInstance ()
getQuality ()
    Get the quality of the compressed image sent to the dashboard
    Returns The quality, from 0 to 100
isAutoCaptureStarted ()
    check if auto capture is started
kPort = 1180
kSize160x120 = 2
kSize320x240 = 1
kSize640x480 = 0

```

**server** = None

**setImage** (*image*)

**setQuality** (*quality*)

Set the quality of the compressed image sent to the dashboard

**Parameters** **quality** – The quality of the JPEG image, from 0 to 100

**setSize** (*size*)

**startAutomaticCapture** (*camera*)

Start automatically capturing images to send to the dashboard.

You should call this method to just see a camera feed on the dashboard without doing any vision processing on the roboRIO. {[@link #setImage](#)} shouldn't be called after this is called.

**Parameters** **camera** – The camera interface (e.g. a USBCamera instance)

## 1.4.2 USBCamera

```
class wpilib._impl.USBCamera (name=None)
```

```
Bases: object
```

```
class WhiteBalance
```

```
Bases: object
```

```
    kFixedFlourescent2 = 5200
```

```
    kFixedFlourescent1 = 5100
```

```
    kFixedIndoor = 3000
```

```
    kFixedOutdoor1 = 4000
```

```
    kFixedOutdoor2 = 5000
```

```
USBCamera.closeCamera ()
```

```
USBCamera.getBrightness ()
```

```
    Get the brightness, as a percentage (0-100).
```

```
USBCamera.getImage (image)
```

```
USBCamera.getImageData (data, maxsize)
```

```
USBCamera.kDefaultCameraName = b'cam0'
```

```
USBCamera.openCamera ()
```

```
USBCamera.setBrightness (brightness)
```

```
    Set the brightness, as a percentage (0-100).
```

```
USBCamera.setExposureAuto ()
```

```
    Set the exposure to auto aperature.
```

```
USBCamera.setExposureHoldCurrent ()
```

```
    Set the exposure to hold current.
```

```
USBCamera.setExposureManual (value)
```

```
    Set the exposure to manual, as a percentage (0-100).
```

```
USBCamera.setFPS (fps)
```

```
USBCamera.setSize (width, height)
```

`USBCamera.setWhiteBalanceAuto()`

Set the white balance to auto.

`USBCamera.setWhiteBalanceHoldCurrent()`

Set the white balance to hold current.

`USBCamera.setWhiteBalanceManual(value)`

Set the white balance to manual, with specified color temperature.

`USBCamera.startCapture()`

`USBCamera.stopCapture()`

`USBCamera.updateSettings()`

**class** `wpiplib._impl.CameraServer`

Bases: `object`

**static** `getInstance()`

`getQuality()`

Get the quality of the compressed image sent to the dashboard

**Returns** The quality, from 0 to 100

`isAutoCaptureStarted()`

check if auto capture is started

`kPort = 1180`

`kSize160x120 = 2`

`kSize320x240 = 1`

`kSize640x480 = 0`

`server = None`

`setImage(image)`

`setQuality(quality)`

Set the quality of the compressed image sent to the dashboard

**Parameters** `quality` – The quality of the JPEG image, from 0 to 100

`setSize(size)`

`startAutomaticCapture(camera)`

Start automatically capturing images to send to the dashboard.

You should call this method to just see a camera feed on the dashboard without doing any vision processing on the roboRIO. `{@link #setImage}` shouldn't be called after this is called.

**Parameters** `camera` – The camera interface (e.g. a `USBCamera` instance)

### 1.4.3 ADXL345\_I2C

**class** `wpiplib.ADXL345_I2C(port, range, address=None)`

Bases: `wpiplib.SensorBase`

ADXL345 accelerometer device via i2c

Constructor.

**Parameters**

- **port** (*I2C.Port*) – The I2C port the accelerometer is attached to.
- **range** (*ADXL345\_I2C.Range*) – The range (+ or -) that the accelerometer will measure.
- **address** – the I2C address of the accelerometer (0x1D or 0x53)

**class Axes**

Bases: object

**kX = 0**

**kY = 2**

**kZ = 4**

**class ADXL345\_I2C.Range**

Bases: object

**k16G = 3**

**k2G = 0**

**k4G = 1**

**k8G = 2**

`ADXL345_I2C.free()`

`ADXL345_I2C.getAcceleration(axis)`

Get the acceleration of one axis in Gs.

**Parameters** *axis* – The axis to read from.

**Returns** An object containing the acceleration measured on each axis of the ADXL345 in Gs.

`ADXL345_I2C.getAccelerations()`

Get the acceleration of all axes in Gs.

**Returns** X,Y,Z tuple of acceleration measured on all axes of the ADXL345 in Gs.

`ADXL345_I2C.getX()`

Get the x axis acceleration

**Returns** The acceleration along the x axis in g-forces

`ADXL345_I2C.getY()`

Get the y axis acceleration

**Returns** The acceleration along the y axis in g-forces

`ADXL345_I2C.getZ()`

Get the z axis acceleration

**Returns** The acceleration along the z axis in g-forces

`ADXL345_I2C.kAddress = 29`

`ADXL345_I2C.kDataFormatRegister = 49`

`ADXL345_I2C.kDataFormat_FullRes = 8`

`ADXL345_I2C.kDataFormat_IntInvert = 32`

`ADXL345_I2C.kDataFormat_Justify = 4`

`ADXL345_I2C.kDataFormat_SPI = 64`

`ADXL345_I2C.kDataFormat_SelfTest = 128`



```

ADXL345_I2C.kDataRegister = 50
ADXL345_I2C.kGsPerLSB = 0.00390625
ADXL345_I2C.kPowerCtlRegister = 45
ADXL345_I2C.kPowerCtl_AutoSleep = 16
ADXL345_I2C.kPowerCtl_Link = 32
ADXL345_I2C.kPowerCtl_Measure = 8
ADXL345_I2C.kPowerCtl_Sleep = 4
ADXL345_I2C.setRange (range)

```

Set the measuring range of the accelerometer.

**Parameters** `range` (`ADXL345_I2C.Range`) – The maximum acceleration, positive or negative, that the accelerometer will measure.

#### 1.4.4 ADXL345\_SPI

```
class wpilib.ADXL345_SPI (port, range)
```

Bases: `wpilib.SensorBase`

ADXL345 accelerometer device via spi

Constructor. Use this when the device is the first/only device on the bus

##### Parameters

- **port** (`SPI.Port`) – The SPI port that the accelerometer is connected to
- **range** (`ADXL345_SPI.Range`) – The range (+ or -) that the accelerometer will measure.

```
class Axes
```

Bases: `object`

```
kX = 0
```

```
kY = 2
```

```
kZ = 4
```

```
class ADXL345_SPI.Range
```

Bases: `object`

```
k16G = 3
```

```
k2G = 0
```

```
k4G = 1
```

```
k8G = 2
```

```
ADXL345_SPI.free ()
```

```
ADXL345_SPI.getAcceleration (axis)
```

Get the acceleration of one axis in Gs.

**Parameters** `axis` – The axis to read from.

**Returns** An object containing the acceleration measured on each axis of the ADXL345 in Gs.

```
ADXL345_SPI.getAccelerations ()
```

Get the acceleration of all axes in Gs.

**Returns** X,Y,Z tuple of acceleration measured on all axes of the ADXL345 in Gs.

`ADXL345_SPI.getX()`

Get the x axis acceleration

**Returns** The acceleration along the x axis in g-forces

`ADXL345_SPI.getY()`

Get the y axis acceleration

**Returns** The acceleration along the y axis in g-forces

`ADXL345_SPI.getZ()`

Get the z axis acceleration

**Returns** The acceleration along the z axis in g-forces

`ADXL345_SPI.kAddress_MultiByte = 64`

`ADXL345_SPI.kAddress_Read = 128`

`ADXL345_SPI.kDataFormatRegister = 49`

`ADXL345_SPI.kDataFormat_FullRes = 8`

`ADXL345_SPI.kDataFormat_IntInvert = 32`

`ADXL345_SPI.kDataFormat_Justify = 4`

`ADXL345_SPI.kDataFormat_SPI = 64`

`ADXL345_SPI.kDataFormat_SelfTest = 128`

`ADXL345_SPI.kDataRegister = 50`

`ADXL345_SPI.kGsPerLSB = 0.00390625`

`ADXL345_SPI.kPowerCtlRegister = 45`

`ADXL345_SPI.kPowerCtl_AutoSleep = 16`

`ADXL345_SPI.kPowerCtl_Link = 32`

`ADXL345_SPI.kPowerCtl_Measure = 8`

`ADXL345_SPI.kPowerCtl_Sleep = 4`

`ADXL345_SPI.setRange(range)`

Set the measuring range of the accelerometer.

**Parameters** `range` (`ADXL345_SPI.Range`) – The maximum acceleration, positive or negative, that the accelerometer will measure.

## 1.4.5 ADXL362

`class wpilib.ADXL362` (`range`, `port=None`)

Bases: `wpilib.SensorBase`

ADXL362 SPI Accelerometer.

This class allows access to an Analog Devices ADXL362 3-axis accelerometer.

Constructor.

**Parameters**

- `range` (`ADXL362.Range`) – The range (+ or -) that the accelerometer will measure.

- **port** (*SPI.Port*) – The SPI port that the accelerometer is connected to

**class Axes**

Bases: object

**kX = 0**

**kY = 2**

**kZ = 4**

**class ADXL362.Range**

Bases: object

**k16G = 3**

**k2G = 0**

**k4G = 1**

**k8G = 2**

ADXL362.**free** ()

ADXL362.**getAcceleration** (*axis*)

Get the acceleration of one axis in Gs.

**Parameters** *axis* – The axis to read from.

**Returns** An object containing the acceleration measured on each axis in Gs.

ADXL362.**getAccelerations** ()

Get the acceleration of all axes in Gs.

**Returns** X,Y,Z tuple of acceleration measured on all axes in Gs.

ADXL362.**getX** ()

Get the x axis acceleration

**Returns** The acceleration along the x axis in g-forces

ADXL362.**getY** ()

Get the y axis acceleration

**Returns** The acceleration along the y axis in g-forces

ADXL362.**getZ** ()

Get the z axis acceleration

**Returns** The acceleration along the z axis in g-forces

ADXL362.**kDataRegister = 14**

ADXL362.**kFilterCtlRegister = 44**

ADXL362.**kFilterCtl\_ODR\_100Hz = 3**

ADXL362.**kFilterCtl\_Range2G = 0**

ADXL362.**kFilterCtl\_Range4G = 64**

ADXL362.**kFilterCtl\_Range8G = 128**

ADXL362.**kPartIdRegister = 2**

ADXL362.**kPowerCtlRegister = 45**

ADXL362.**kPowerCtl\_AutoSleep = 4**

```
ADXL362.kPowerCtl_Measure = 2
ADXL362.kPowerCtl_UltraLowNoise = 32
ADXL362.kRegRead = 11
ADXL362.kRegWrite = 10
ADXL362.setRange(range)
```

Set the measuring range of the accelerometer.

**Parameters** *range* (*ADXL362.Range*) – The maximum acceleration, positive or negative, that the accelerometer will measure.

## 1.4.6 ADXRS450\_Gyro

```
class wpilib.ADXRS450_Gyro(port=None)
```

Bases: *wpilib.GyroBase*

Use a rate gyro to return the robots heading relative to a starting position. The Gyro class tracks the robots heading based on the starting position. As the robot rotates the new heading is computed by integrating the rate of rotation returned by the sensor. When the class is instantiated, it does a short calibration routine where it samples the gyro while at rest to determine the default offset. This is subtracted from each sample to determine the heading.

This class is for the digital ADXRS450 gyro sensor that connects via SPI.

Constructor.

**Parameters** *port* (*SPI.Port*) – The SPI port that the gyro is connected to

```
calibrate()
```

```
free()
```

Delete (free) the spi port used for the gyro and stop accumulating.

```
getAngle()
```

```
getRate()
```

```
kCalibrationSampleTime = 5.0
```

```
kDegreePerSecondPerLSB = 0.0125
```

```
kFaultRegister = 10
```

```
kHiCSTRegister = 6
```

```
kLoCSTRegister = 4
```

```
kPIDRegister = 12
```

```
kQuadRegister = 8
```

```
kRateRegister = 0
```

```
kSNHighRegister = 14
```

```
kSNLowRegister = 16
```

```
kSamplePeriod = 0.001
```

```
kTemRegister = 2
```

```
reset()
```

## 1.4.7 AnalogAccelerometer

**class** `wpiplib.AnalogAccelerometer` (*channel*)

Bases: `wpiplib.LiveWindowSendable`

Analog Accelerometer

The accelerometer reads acceleration directly through the sensor. Many sensors have multiple axis and can be treated as multiple devices. Each is calibrated by finding the center value over a period of time.

Constructor. Create a new instance of Accelerometer from either an existing AnalogChannel or from an analog channel port index.

**Parameters** `channel` – port index or an already initialized `AnalogInput`

**class** `PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement** = 0

**kRate** = 1

`AnalogAccelerometer.free()`

`AnalogAccelerometer.getAcceleration()`

Return the acceleration in Gs.

The acceleration is returned units of Gs.

**Returns** The current acceleration of the sensor in Gs.

**Return type** `float`

`AnalogAccelerometer.getPIDSourceType()`

`AnalogAccelerometer.pidGet()`

Get the Acceleration for the PID Source parent.

**Returns** The current acceleration in Gs.

**Return type** `float`

`AnalogAccelerometer.setPIDSourceType(pidSource)`

Set which parameter you are using as a process control variable.

**Parameters** `pidSource` (`PIDSource.PIDSourceType`) – An enum to select the parameter.

`AnalogAccelerometer.setSensitivity(sensitivity)`

Set the accelerometer sensitivity.

This sets the sensitivity of the accelerometer used for calculating the acceleration. The sensitivity varies by accelerometer model. There are constants defined for various models.

**Parameters** `sensitivity` (`float`) – The sensitivity of accelerometer in Volts per G.

`AnalogAccelerometer.setZero(zero)`

Set the voltage that corresponds to 0 G.

The zero G voltage varies by accelerometer model. There are constants defined for various models.

**Parameters** `zero` (`float`) – The zero G voltage.

## 1.4.8 AnalogGyro

**class** `wpiplib.AnalogGyro` (*channel*, *center=None*, *offset=None*)

Bases: `wpiplib.GyroBase`

Interface to a gyro device via an `AnalogInput`

Use a rate gyro to return the robots heading relative to a starting position. The Gyro class tracks the robots heading based on the starting position. As the robot rotates the new heading is computed by integrating the rate of rotation returned by the sensor. When the class is instantiated, it does a short calibration routine where it samples the gyro while at rest to determine the default offset. This is subtracted from each sample to determine the heading.

Gyro constructor.

Also initializes the gyro. Calibrate the gyro by running for a number of samples and computing the center value. Then use the center value as the Accumulator center value for subsequent measurements. It's important to make sure that the robot is not moving while the centering calculations are in progress, this is typically done when the robot is first turned on while it's sitting at rest before the competition starts.

### Parameters

- **channel** – The analog channel index or `AnalogInput` object that the gyro is connected to. Gyros can only be used on on-board channels 0-1.
- **center** (*int*) – Preset uncalibrated value to use as the accumulator center value
- **offset** (*float*) – Preset uncalibrated value to use as the gyro offset

**class** `PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement = 0**

**kRate = 1**

`AnalogGyro.calibrate()`

See `Gyro.calibrate()`

`AnalogGyro.free()`

See `Gyro.free()`

`AnalogGyro.getAngle()`

See `Gyro.getAngle()`

`AnalogGyro.getCenter()`

Return the gyro center value set during calibration to use as a future preset

**Returns** the current center value

`AnalogGyro.getOffset()`

Return the gyro offset value set during calibration to use as a future preset

**Returns** the current offset value

`AnalogGyro.getRate()`

See `Gyro.getRate()`

`AnalogGyro.kAverageBits = 0`

`AnalogGyro.kCalibrationSampleTime = 5.0`

```
AnalogGyro.kDefaultVoltsPerDegreePerSecond = 0.007
```

```
AnalogGyro.kOversampleBits = 10
```

```
AnalogGyro.kSamplesPerSecond = 50.0
```

```
AnalogGyro.reset ()
```

See `Gyro.reset ()`

```
AnalogGyro.setDeadband (volts)
```

Set the size of the neutral zone. Any voltage from the gyro less than this amount from the center is considered stationary. Setting a deadband will decrease the amount of drift when the gyro isn't rotating, but will make it less accurate.

**Parameters** `volts` (*float*) – The size of the deadband in volts

```
AnalogGyro.setSensitivity (voltsPerDegreePerSecond)
```

Set the gyro sensitivity. This takes the number of volts/degree/second sensitivity of the gyro and uses it in subsequent calculations to allow the code to work with multiple gyros. This value is typically found in the gyro datasheet.

**Parameters** `voltsPerDegreePerSecond` (*float*) – The sensitivity in Volts/degree/second

## 1.4.9 AnalogInput

```
class wpilib.AnalogInput (channel)
```

Bases: `wpilib.SensorBase`

Analog input

Each analog channel is read from hardware as a 12-bit number representing 0V to 5V.

Connected to each analog channel is an averaging and oversampling engine. This engine accumulates the specified (by `setAverageBits ()` and `setOversampleBits ()`) number of samples before returning a new value. This is not a sliding window average. The only difference between the oversampled samples and the averaged samples is that the oversampled samples are simply accumulated effectively increasing the resolution, while the averaged samples are divided by the number of samples to retain the resolution, but get more stable values.

Construct an analog channel. :param channel: The channel number to represent. 0-3 are on-board 4-7 are on the MXP port.

```
class PIDSourceType
```

Bases: `object`

A description for the type of output value to provide to a `PIDController`

```
kDisplacement = 0
```

```
kRate = 1
```

```
AnalogInput.channels = <wpilib.resource.Resource object>
```

```
AnalogInput.free ()
```

```
AnalogInput.getAccumulatorCount ()
```

Read the number of accumulated values.

Read the count of the accumulated values since the accumulator was last `reset ()`.

**Returns** The number of times samples from the channel were accumulated.

`AnalogInput.getAccumulatorOutput()`

Read the accumulated value and the number of accumulated values atomically.

This function reads the value and count from the FPGA atomically. This can be used for averaging.

**Returns** tuple of (value, count)

`AnalogInput.getAccumulatorValue()`

Read the accumulated value.

Read the value that has been accumulating. The accumulator is attached after the oversample and average engine.

**Returns** The 64-bit value accumulated since the last `reset()`.

`AnalogInput.getAverageBits()`

Get the number of averaging bits. This gets the number of averaging bits from the FPGA. The actual number of averaged samples is  $2^{\text{bits}}$ . The averaging is done automatically in the FPGA.

**Returns** The number of averaging bits.

`AnalogInput.getAverageValue()`

Get a sample from the output of the oversample and average engine for this channel. The sample is 12-bit + the bits configured in `setOversampleBits()`. The value configured in `setAverageBits()` will cause this value to be averaged  $2^{\text{bits}}$  number of samples. This is not a sliding window. The sample will not change until  $2^{(\text{OversampleBits} + \text{AverageBits})}$  samples have been acquired from this channel. Use `getAverageVoltage()` to get the analog value in calibrated units.

**Returns** A sample from the oversample and average engine for this channel.

`AnalogInput.getAverageVoltage()`

Get a scaled sample from the output of the oversample and average engine for this channel. The value is scaled to units of Volts using the calibrated scaling data from `getLSBWeight()` and `getOffset()`. Using oversampling will cause this value to be higher resolution, but it will update more slowly. Using averaging will cause this value to be more stable, but it will update more slowly.

**Returns** A scaled sample from the output of the oversample and average engine for this channel.

`AnalogInput.getChannel()`

Get the channel number.

**Returns** The channel number.

**static** `AnalogInput.getGlobalSampleRate()`

Get the current sample rate.

This assumes one entry in the scan list. This is a global setting for all channels.

**Returns** Sample rate.

`AnalogInput.getLSBWeight()`

Get the factory scaling least significant bit weight constant. The least significant bit weight constant for the channel that was calibrated in manufacturing and stored in an eeprom.

$\text{Volts} = ((\text{LSB\_Weight} * 1\text{e-}9) * \text{raw}) - (\text{Offset} * 1\text{e-}9)$

**Returns** Least significant bit weight.

`AnalogInput.getOffset()`

Get the factory scaling offset constant. The offset constant for the channel that was calibrated in manufacturing and stored in an eeprom.

$\text{Volts} = ((\text{LSB\_Weight} * 1\text{e-}9) * \text{raw}) - (\text{Offset} * 1\text{e-}9)$

**Returns** Offset constant.



`AnalogInput.getOversampleBits()`

Get the number of oversample bits. This gets the number of oversample bits from the FPGA. The actual number of oversampled values is  $2^{\text{bits}}$ . The oversampling is done automatically in the FPGA.

**Returns** The number of oversample bits.

`AnalogInput.getPIDSourceType()`

See `PIDSource.getPIDSourceType()`

`AnalogInput.getValue()`

Get a sample straight from this channel. The sample is a 12-bit value representing the 0V to 5V range of the A/D converter. The units are in A/D converter codes. Use `getVoltage()` to get the analog value in calibrated units.

**Returns** A sample straight from this channel.

`AnalogInput.getVoltage()`

Get a scaled sample straight from this channel. The value is scaled to units of Volts using the calibrated scaling data from `getLSBWeight()` and `getOffset()`.

**Returns** A scaled sample straight from this channel.

`AnalogInput.initAccumulator()`

Initialize the accumulator.

`AnalogInput.isAccumulatorChannel()`

Is the channel attached to an accumulator.

**Returns** The analog channel is attached to an accumulator.

`AnalogInput.kAccumulatorChannels = (0, 1)`

`AnalogInput.kAccumulatorSlot = 1`

`AnalogInput.pidGet()`

Get the average voltage for use with PIDController

**Returns** the average voltage

`AnalogInput.port`

`AnalogInput.resetAccumulator()`

Resets the accumulator to the initial value.

`AnalogInput.setAccumulatorCenter(center)`

Set the center value of the accumulator.

The center value is subtracted from each A/D value before it is added to the accumulator. This is used for the center value of devices like gyros and accelerometers to make integration work and to take the device offset into account when integrating.

This center value is based on the output of the oversampled and averaged source from channel 1. Because of this, any non-zero oversample bits will affect the size of the value for this field.

`AnalogInput.setAccumulatorDeadband(deadband)`

Set the accumulator's deadband.

`AnalogInput.setAccumulatorInitialValue(initialValue)`

Set an initial value for the accumulator.

This will be added to all values returned to the user.

**Parameters** `initialValue` – The value that the accumulator should start from when reset.

`AnalogInput.setAverageBits(bits)`

Set the number of averaging bits. This sets the number of averaging bits. The actual number of averaged samples is  $2^{\text{bits}}$ . The averaging is done automatically in the FPGA.

**Parameters** `bits` – The number of averaging bits.

`static AnalogInput.setGlobalSampleRate(samplesPerSecond)`

Set the sample rate per channel.

This is a global setting for all channels. The maximum rate is 500kS/s divided by the number of channels in use. This is 62500 samples/s per channel if all 8 channels are used.

**Parameters** `samplesPerSecond` – The number of samples per second.

`AnalogInput.setOversampleBits(bits)`

Set the number of oversample bits. This sets the number of oversample bits. The actual number of oversampled values is  $2^{\text{bits}}$ . The oversampling is done automatically in the FPGA.

**Parameters** `bits` – The number of oversample bits.

`AnalogInput.setPIDSourceType(pidSource)`

See `PIDSource.setPIDSourceType()`

## 1.4.10 AnalogOutput

`class wpilib.AnalogOutput(channel)`

Bases: `wpilib.SensorBase`

Analog output

Construct an analog output on a specified MXP channel.

**Parameters** `channel` – The channel number to represent.

`channels = <wpilib.resource.Resource object>`

`free()`

Channel destructor.

`getVoltage()`

`port`

`setVoltage(voltage)`

## 1.4.11 AnalogPotentiometer

`class wpilib.AnalogPotentiometer(channel, fullRange=1.0, offset=0.0)`

Bases: `wpilib.LiveWindowSendable`

Reads a potentiometer via an `AnalogInput`

Analog potentiometers read in an analog voltage that corresponds to a position. The position is in whichever units you choose, by way of the scaling and offset constants passed to the constructor.

AnalogPotentiometer constructor.

Use the `fullRange` and `offset` values so that the output produces meaningful values. I.E: you have a 270 degree potentiometer and you want the output to be degrees with the halfway point as 0 degrees. The `fullRange` value is 270.0(degrees) and the `offset` is -135.0 since the halfway point after scaling is 135 degrees.

**Parameters**

- **channel** (int or *AnalogInput*) – The analog channel this potentiometer is plugged into.
- **fullRange** (*float*) – The scaling to multiply the fraction by to get a meaningful unit. Defaults to 1.0 if unspecified.
- **offset** (*float*) – The offset to add to the scaled value for controlling the zero value. Defaults to 0.0 if unspecified.

#### class **PIDSourceType**

Bases: object

A description for the type of output value to provide to a *PIDController*

**kDisplacement = 0**

**kRate = 1**

*AnalogPotentiometer*.**free**()

*AnalogPotentiometer*.**get**()

Get the current reading of the potentiometer.

**Returns** The current position of the potentiometer.

**Return type** float

*AnalogPotentiometer*.**getPIDSourceType**()

*AnalogPotentiometer*.**pidGet**()

Implement the PIDSource interface.

**Returns** The current reading.

**Return type** float

*AnalogPotentiometer*.**setPIDSourceType**(*pidSource*)

Set which parameter you are using as a process control variable.

**Parameters** **pidSource** (*PIDSource.PIDSourceType*) – An enum to select the parameter.

### 1.4.12 AnalogTrigger

class **wpiplib.AnalogTrigger**(*channel*)

Bases: object

Converts an analog signal into a digital signal

An analog trigger is a way to convert an analog signal into a digital signal using resources built into the FPGA. The resulting digital signal can then be used directly or fed into other digital components of the FPGA such as the counter or encoder modules. The analog trigger module works by comparing analog signals to a voltage range set by the code. The specific return types and meanings depend on the analog trigger mode in use.

Constructor for an analog trigger given a channel number or analog input.

**Parameters** **channel** – the port index or *AnalogInput* to use for the analog trigger. Treated as an *AnalogInput* if the provided object has a *getChannel* function.

class **AnalogTriggerType**

Bases: object

Defines the state in which the *AnalogTrigger* triggers

**kFallingPulse = 3**

**kInWindow = 0**

**kRisingPulse = 2**

**kState = 1**

`AnalogTrigger.createOutput` (*type*)

Creates an *AnalogTriggerOutput* object. Gets an output object that can be used for routing. Caller is responsible for deleting the *AnalogTriggerOutput* object.

**Parameters** *type* – An enum of the type of output object to create.

**Returns** An *AnalogTriggerOutput* object.

`AnalogTrigger.free` ()

Release the resources used by this object

`AnalogTrigger.getInWindow` ()

Return the InWindow output of the analog trigger. True if the analog input is between the upper and lower limits.

**Returns** The InWindow output of the analog trigger.

`AnalogTrigger.getIndex` ()

Return the index of the analog trigger. This is the FPGA index of this analog trigger instance.

**Returns** The index of the analog trigger.

`AnalogTrigger.getTriggerState` ()

Return the TriggerState output of the analog trigger. True if above upper limit. False if below lower limit. If in Hysteresis, maintain previous state.

**Returns** The TriggerState output of the analog trigger.

`AnalogTrigger.port`

`AnalogTrigger.setAveraged` (*useAveragedValue*)

Configure the analog trigger to use the averaged vs. raw values. If the value is true, then the averaged value is selected for the analog trigger, otherwise the immediate value is used.

**Parameters** *useAveragedValue* – True to use an averaged value, False otherwise

`AnalogTrigger.setFiltered` (*useFilteredValue*)

Configure the analog trigger to use a filtered value. The analog trigger will operate with a 3 point average rejection filter. This is designed to help with 360 degree pot applications for the period where the pot crosses through zero.

**Parameters** *useFilteredValue* – True to use a filterd value, False otherwise

`AnalogTrigger.setLimitsRaw` (*lower, upper*)

Set the upper and lower limits of the analog trigger. The limits are given in ADC codes. If oversampling is used, the units must be scaled appropriately.

**Parameters**

- **lower** – the lower raw limit
- **upper** – the upper raw limit

`AnalogTrigger.setLimitsVoltage` (*lower, upper*)

Set the upper and lower limits of the analog trigger. The limits are given as floating point voltage values.

**Parameters**

- **lower** – the lower voltage limit

- **upper** – the upper voltage limit

### 1.4.13 AnalogTriggerOutput

**class** `wpiplib.AnalogTriggerOutput` (*trigger, outputType*)

Bases: `object`

Represents a specific output from an *AnalogTrigger*

This class is used to get the current output value and also as a *DigitalSource* to provide routing of an output to digital subsystems on the FPGA such as *Counter*, `Encoder.`, and `:class:Interrupt`.

The `TriggerState` output indicates the primary output value of the trigger. If the analog signal is less than the lower limit, the output is `False`. If the analog value is greater than the upper limit, then the output is `True`. If the analog value is in between, then the trigger output state maintains its most recent value.

The `InWindow` output indicates whether or not the analog signal is inside the range defined by the limits.

The `RisingPulse` and `FallingPulse` outputs detect an instantaneous transition from above the upper limit to below the lower limit, and vice versa. These pulses represent a rollover condition of a sensor and can be routed to an up / down counter or to interrupts. Because the outputs generate a pulse, they cannot be read directly. To help ensure that a rollover condition is not missed, there is an average rejection filter available that operates on the upper 8 bits of a 12 bit number and selects the nearest outlier of 3 samples. This will reject a sample that is (due to averaging or sampling) errantly between the two limits. This filter will fail if more than one sample in a row is errantly in between the two limits. You may see this problem if attempting to use this feature with a mechanical rollover sensor, such as a 360 degree no-stop potentiometer without signal conditioning, because the rollover transition is not sharp / clean enough. Using the averaging engine may help with this, but rotational speeds of the sensor will then be limited.

Create an object that represents one of the four outputs from an analog trigger.

Because this class derives from `DigitalSource`, it can be passed into routing functions for `Counter`, `Encoder`, etc.

#### Parameters

- **trigger** – The trigger for which this is an output.
- **outputType** – An enum that specifies the output on the trigger to represent.

**class** `AnalogTriggerType`

Bases: `object`

Defines the state in which the *AnalogTrigger* triggers

**kFallingPulse = 3**

**kInWindow = 0**

**kRisingPulse = 2**

**kState = 1**

`AnalogTriggerOutput.free()`

`AnalogTriggerOutput.get()`

Get the state of the analog trigger output.

**Returns** The state of the analog trigger output.

**Return type** *AnalogTriggerType*

`AnalogTriggerOutput.getAnalogTriggerForRouting()`

`AnalogTriggerOutput.getChannelForRouting()`

AnalogTriggerOutput.**getModuleForRouting**()

### 1.4.14 BuiltInAccelerometer

**class** wpilib.**BuiltInAccelerometer** (*range=2*)

Bases: *wpilib.LiveWindowSendable*

Built-in accelerometer device

This class allows access to the RoboRIO's internal accelerometer.

Constructor.

**Parameters** *range* (*Accelerometer.Range*) – The range the accelerometer will measure. Defaults to +/-8g if unspecified.

**class** **Range**

Bases: object

**k16G = 3**

**k2G = 0**

**k4G = 1**

**k8G = 2**

BuiltInAccelerometer.**free**()

BuiltInAccelerometer.**getX**()

**Returns** The acceleration of the RoboRIO along the X axis in g-forces

**Return type** float

BuiltInAccelerometer.**getY**()

**Returns** The acceleration of the RoboRIO along the Y axis in g-forces

**Return type** float

BuiltInAccelerometer.**getZ**()

**Returns** The acceleration of the RoboRIO along the Z axis in g-forces

**Return type** float

BuiltInAccelerometer.**setRange** (*range*)

Set the measuring range of the accelerometer.

**Parameters** *range* (*BuiltInAccelerometer.Range*) – The maximum acceleration, positive or negative, that the accelerometer will measure.

### 1.4.15 CANJaguar

**class** wpilib.**CANJaguar** (*deviceNumber*)

Bases: *wpilib.LiveWindowSendable*, *wpilib.MotorSafety*

Texas Instruments Jaguar Speed Controller as a CAN device.

Constructor for the CANJaguar device.

By default the device is configured in Percent mode. The control mode can be changed by calling one of the control mode functions.

**Parameters** `deviceNumber` – The address of the Jaguar on the CAN bus.

**class** `ControlMode`

Bases: `object`

Determines how the Jaguar is controlled, used internally.

**Current = 1**

**PercentVbus = 0**

**Position = 3**

**Speed = 2**

**Voltage = 4**

**class** `CANJaguar.LimitMode`

Bases: `object`

Determines which sensor to use for position reference. Limit switches will always be used to limit the rotation. This can not be disabled.

**SoftPositionLimits = 1**

Enables the soft position limits on the Jaguar. These will be used in addition to the limit switches. This does not disable the behavior of the limit switch input. See `configSoftPositionLimits()`.

**SwitchInputsOnly = 0**

Disables the soft position limits and only uses the limit switches to limit rotation. See `getForwardLimitOK()` and `getReverseLimitOK()`.

**class** `CANJaguar.Mode`

Bases: `object`

Control Mode.

**kEncoder = 0**

Sets an encoder as the speed reference only.

**kPotentiometer = 2**

Sets a potentiometer as the position reference only.

**kQuadEncoder = 1**

Sets a quadrature encoder as the position and speed reference.

**class** `CANJaguar.NeutralMode`

Bases: `object`

Determines how the Jaguar behaves when sending a zero signal.

**Brake = 1**

Stop the motor's rotation by applying a force.

**Coast = 2**

Do not attempt to stop the motor. Instead allow it to coast to a stop without applying resistance.

**Jumper = 0**

Use the NeutralMode that is set by the jumper wire on the CAN device

`CANJaguar.allocated = <wpilib.resource.Resource object>`

`CANJaguar.changeControlMode (controlMode)`

Used internally. In order to set the control mode see the methods listed below.

Change the control mode of this Jaguar object.

After changing modes, configure any PID constants or other settings needed and then `EnableControl()` to actually change the mode on the Jaguar.

**Parameters** `controlMode` – The new mode.

`CANJaguar.configEncoderCodesPerRev` (*codesPerRev*)

Configure how many codes per revolution are generated by your encoder.

**Parameters** `codesPerRev` – The number of counts per revolution in 1X mode.

`CANJaguar.configFaultTime` (*faultTime*)

Configure how long the Jaguar waits in the case of a fault before resuming operation.

Faults include over temperature, over current, and bus under voltage. The default is 3.0 seconds, but can be reduced to as low as 0.5 seconds.

**Parameters** `faultTime` – The time to wait before resuming operation, in seconds.

`CANJaguar.configForwardLimit` (*forwardLimitPosition*)

Set the position that, if exceeded, will disable the forward direction.

Use `configSoftPositionLimits()` to set this and the *LimitMode* automatically.

**Parameters** `forwardLimitPosition` – The position that, if exceeded, will disable the forward direction.

`CANJaguar.configLimitMode` (*mode*)

Set the limit mode for position control mode.<br>

Use `configSoftPositionLimits()` or `disableSoftPositionLimits()` to set this automatically.

**Parameters** `mode` – The *LimitMode* to use to limit the rotation of the device.

`CANJaguar.configMaxOutputVoltage` (*voltage*)

Configure the maximum voltage that the Jaguar will ever output.

This can be used to limit the maximum output voltage in all modes so that motors which cannot withstand full bus voltage can be used safely.

**Parameters** `voltage` – The maximum voltage output by the Jaguar.

`CANJaguar.configNeutralMode` (*mode*)

Configure what the controller does to the H-Bridge when neutral (not driving the output).

This allows you to override the jumper configuration for brake or coast.

**Parameters** `mode` – Select to use the jumper setting or to override it to coast or brake (see *NeutralMode*).

`CANJaguar.configPotentiometerTurns` (*turns*)

Configure the number of turns on the potentiometer.

There is no special support for continuous turn potentiometers. Only integer numbers of turns are supported.

**Parameters** `turns` – The number of turns of the potentiometer

`CANJaguar.configReverseLimit` (*reverseLimitPosition*)

Set the position that, if exceeded, will disable the reverse direction.

Use `configSoftPositionLimits()` to set this and the *LimitMode* automatically.

**Parameters** `reverseLimitPosition` – The position that, if exceeded, will disable the reverse direction.



`CANJaguar.configSoftPositionLimits` (*forwardLimitPosition, reverseLimitPosition*)

Configure Soft Position Limits when in Position Controller mode.

When controlling position, you can add additional limits on top of the limit switch inputs that are based on the position feedback. If the position limit is reached or the switch is opened, that direction will be disabled.

#### Parameters

- **forwardLimitPosition** – The position that, if exceeded, will disable the forward direction.
- **reverseLimitPosition** – The position that, if exceeded, will disable the reverse direction.

`CANJaguar.disable` ()

Common interface for disabling a motor.

Deprecated since version 2015: Use `disableControl` () instead.

`CANJaguar.disableControl` ()

Disable the closed loop controller.

Stop driving the output based on the feedback.

`CANJaguar.disableSoftPositionLimits` ()

Disable Soft Position Limits if previously enabled.<br>

Soft Position Limits are disabled by default.

`CANJaguar.enableControl` (*encoderInitialPosition=0.0*)

Enable the closed loop controller.

Start actually controlling the output based on the feedback. If starting a position controller with an encoder reference, use the `encoderInitialPosition` parameter to initialize the encoder state.

**Parameters** **encoderInitialPosition** – Encoder position to set if position with encoder reference (default of 0.0). Ignored otherwise.

`CANJaguar.free` ()

Cancel periodic messages to the Jaguar, effectively disabling it. No other methods should be called after this is called.

`CANJaguar.get` ()

Get the recently set `outputValue` set point.

The scale and the units depend on the mode the Jaguar is in.

- In `percentVbus` mode, the `outputValue` is from -1.0 to 1.0 (same as PWM Jaguar).
- In `voltage` mode, the `outputValue` is in volts.
- In `current` mode, the `outputValue` is in amps.
- In `speed` mode, the `outputValue` is in rotations/minute.
- In `position` mode, the `outputValue` is in rotations.

**Returns** The most recently set `outputValue` set point.

`CANJaguar.getBusVoltage` ()

Get the voltage at the battery input terminals of the Jaguar.

**Returns** The bus voltage in Volts.

`CANJaguar.getControlMode()`

Get the active control mode from the Jaguar.

Ask the Jaguar what mode it is in.

**Returns** `ControlMode` that the Jag is in.

`CANJaguar.getD()`

Get the Derivative gain of the controller.

**Returns** The derivative gain.

`CANJaguar.getDescription()`

`CANJaguar.getDeviceID()`

`CANJaguar.getDeviceNumber()`

**Returns** The CAN ID passed in the constructor

`CANJaguar.getError()`

Get the difference between the setpoint and goal in closed loop modes.

Outside of position and velocity modes the return value of `getError()` has relatively little meaning.

**Returns** The difference between the setpoint and the current position.

`CANJaguar.getFaults()`

Get the status of any faults the Jaguar has detected.

**Returns**

A bit-mask of faults defined by the “Faults” constants.

- *kCurrentFault*
- *kBusVoltageFault*
- *kTemperatureFault*
- *GateDriverFault*

`CANJaguar.getFirmwareVersion()`

Get the version of the firmware running on the Jaguar.

**Returns** The firmware version. 0 if the device did not respond.

`CANJaguar.getForwardLimitOK()`

Get the status of the forward limit switch.

**Returns** True if the motor is allowed to turn in the forward direction.

`CANJaguar.getHardwareVersion()`

Get the version of the Jaguar hardware.

**Returns** The hardware version. 1: Jaguar, 2: Black Jaguar

`CANJaguar.getI()`

Get the Integral gain of the controller.

**Returns** The integral gain.

`CANJaguar.getInverted()`

Common interface for the inverting direction of a speed controller.

**Returns** The state of inversion (True is inverted).

`CANJaguar.getMessage(messageID, messageMask)`

Get a previously requested message.

Jaguar always generates a message with the same message ID when replying.

**Parameters** `messageID` – The messageID to read from the CAN bus (device number is added internally)

**Returns** The up to 8 bytes of data that was received with the message

`CANJaguar.getOutputCurrent()`

Get the current through the motor terminals of the Jaguar.

**Returns** The output current in Amps.

`CANJaguar.getOutputVoltage()`

Get the voltage being output from the motor terminals of the Jaguar.

**Returns** The output voltage in Volts.

`CANJaguar.getP()`

Get the Proportional gain of the controller.

**Returns** The proportional gain.

`CANJaguar.getPosition()`

Get the position of the encoder or potentiometer.

**Returns** The position of the motor in rotations based on the configured feedback. See `configPotentiometerTurns()` and `configEncoderCodesPerRev()`.

`CANJaguar.getReverseLimitOK()`

Get the status of the reverse limit switch.

**Returns** True if the motor is allowed to turn in the reverse direction.

`CANJaguar.getSetpoint()`

Equivalent to `get()`

`CANJaguar.getSpeed()`

Get the speed of the encoder.

**Returns** The speed of the motor in RPM based on the configured feedback.

`CANJaguar.getTemperature()`

Get the internal temperature of the Jaguar.

**Returns** The temperature of the Jaguar in degrees Celsius.

`CANJaguar.isEnabled()`

Return whether the controller is enabled.

**Returns** True if enabled

`CANJaguar.kApproxBusVoltage = 12.0`

`CANJaguar.kBusVoltageFault = 4`

`CANJaguar.kControllerRate = 1000`

`CANJaguar.kCurrentFault = 1`

`CANJaguar.kForwardLimit = 1`

`CANJaguar.kFullMessageIDMask = 536870848`

`CANJaguar.kGateDriverFault = 8`

`CANJaguar.kMaxMessageDataSize = 8`

`CANJaguar.kReceiveStatusAttempts = 50`

`CANJaguar.kReverseLimit = 2`

`CANJaguar.kSendMessagePeriod = 20`

`CANJaguar.kTemperatureFault = 2`

`CANJaguar.kTrustedMessages = {33685760, 33685824, 33686976, 33687040, 33687872, 33687936, 33689024, 33689088}`

`CANJaguar.pidWrite (output)`

`CANJaguar.requestMessage (messageID, period=0)`

Request a message from the Jaguar, but don't wait for it to arrive.

#### Parameters

- **messageID** – The message to request
- **periodic** – If positive, tell Network Communications to request the message every “period” milliseconds.

`CANJaguar.reset ()`

`CANJaguar.sendMessage (messageID, data, period=0)`

Send a message to the Jaguar.

#### Parameters

- **messageID** – The messageID to be used on the CAN bus (device number is added internally)
- **data** – The up to 8 bytes of data to be sent with the message
- **period** – If positive, tell Network Communications to send the message every “period” milliseconds.

`CANJaguar.set (outputValue, syncGroup=0)`

Sets the output set-point value.

The scale and the units depend on the mode the Jaguar is in.

- In percentVbus Mode, the outputValue is from -1.0 to 1.0 (same as PWM Jaguar).
- In voltage Mode, the outputValue is in volts.
- In current Mode, the outputValue is in amps.
- In speed mode, the outputValue is in rotations/minute.
- In position Mode, the outputValue is in rotations.

#### Parameters

- **outputValue** – The set-point to sent to the motor controller.
- **syncGroup** – The update group to add this set() to, pending UpdateSyncGroup(). If 0 (default), update immediately.

`CANJaguar.setCurrentModeEncoder (codesPerRev, p, i, d)`

Enable controlling the motor current with a PID loop, and enable speed sensing from a non-quadrature encoder.

After calling this you must call `enableControl ()` to enable the device.

**Parameters**

- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setCurrentModePID(p, i, d)`

Enable controlling the motor current with a PID loop.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setCurrentModePotentiometer(p, i, d)`

Enable controlling the motor current with a PID loop, and enable position sensing from a potentiometer.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setCurrentModeQuadEncoder(codesPerRev, p, i, d)`

Enable controlling the motor current with a PID loop, and enable speed and position sensing from a quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **codesPerRev** – The counts per revolution on the encoder
- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setD(d)`

Set the D constant for the closed loop modes.

**Parameters** **d** – The derivative gain of the Jaguar’s PID controller.

`CANJaguar.setI(i)`

Set the I constant for the closed loop modes.

**Parameters** **i** – The integral gain of the Jaguar’s PID controller.

`CANJaguar.setInverted(isInverted)`

Inverts the direction of rotation of the motor. Only works in percentVbus, Speed, and Voltage modes.

**Parameters** **isInverted** – The state of inversion (True is inverted).

`CANJaguar.setP(p)`

Set the P constant for the closed loop modes.

**Parameters** **p** – The proportional gain of the Jaguar’s PID controller.

`CANJaguar.setPID(p, i, d)`

Set the P, I, and D constants for the closed loop modes.

**Parameters**

- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setPercentMode()`

Enable controlling the motor voltage as a percentage of the bus voltage without any position or speed feedback.

After calling this you must call `enableControl()` to enable the device.

`CANJaguar.setPercentModeEncoder(codesPerRev)`

Enable controlling the motor voltage as a percentage of the bus voltage, and enable speed sensing from a non-quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters** `codesPerRev` – The counts per revolution on the encoder

`CANJaguar.setPercentModePotentiometer()`

Enable controlling the motor voltage as a percentage of the bus voltage, and enable position sensing from a potentiometer and no speed feedback.

After calling this you must call `enableControl()` to enable the device.

**Parameters** `tag` – The constant {`@link CANJaguar#kPotentiometer`}

`CANJaguar.setPercentModeQuadEncoder(codesPerRev)`

Enable controlling the motor voltage as a percentage of the bus voltage, and enable position and speed sensing from a quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- `tag` – The constant {`@link CANJaguar#kQuadEncoder`}
- `codesPerRev` – The counts per revolution on the encoder

`CANJaguar.setPositionModePotentiometer(p, i, d)`

Enable controlling the position with a feedback loop using a potentiometer.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setPositionModeQuadEncoder(codesPerRev, p, i, d)`

Enable controlling the position with a feedback loop using an encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- `codesPerRev` – The counts per revolution on the encoder
- **p** – The proportional gain of the Jaguar’s PID controller.

- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setPositionReference` (*reference*)

Set the reference source device for position controller mode.

Choose between using an encoder and using a potentiometer as the source of position feedback when in position control mode.

**Parameters** *reference* – Specify a position reference.

`CANJaguar.setSetpoint` (*value*)

Equivalent to `set()`. Implements `PIDInterface`.

`CANJaguar.setSpeedModeEncoder` (*codesPerRev, p, i, d*)

Enable controlling the speed with a feedback loop from a non-quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **codesPerRev** – The counts per revolution on the encoder
- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setSpeedModeQuadEncoder` (*codesPerRev, p, i, d*)

Enable controlling the speed with a feedback loop from a quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

**Parameters**

- **codesPerRev** – The counts per revolution on the encoder
- **p** – The proportional gain of the Jaguar’s PID controller.
- **i** – The integral gain of the Jaguar’s PID controller.
- **d** – The differential gain of the Jaguar’s PID controller.

`CANJaguar.setSpeedReference` (*reference*)

Set the reference source device for speed controller mode.

Choose encoder as the source of speed feedback when in speed control mode.

**Parameters** *reference* – Specify a speed reference.

`CANJaguar.setVoltageMode` ()

Enable controlling the motor voltage without any position or speed feedback.

After calling this you must call `enableControl()` to enable the device.

`CANJaguar.setVoltageModeEncoder` (*codesPerRev*)

Enable controlling the motor voltage with speed feedback from a non-quadrature encoder and no position feedback.

After calling this you must call `enableControl()` to enable the device.

**Parameters** *codesPerRev* – The counts per revolution on the encoder

`CANJaguar.setVoltageModePotentiometer` ()

Enable controlling the motor voltage with position feedback from a potentiometer and no speed feedback.

After calling this you must call `enableControl()` to enable the device.

`CANJaguar.setVoltageModeQuadEncoder(codesPerRev)`

Enable controlling the motor voltage with position and speed feedback from a quadrature encoder.

After calling this you must call `enableControl()` to enable the device.

#### Parameters

- **tag** – The constant `{@link CANJaguar#kQuadEncoder}`
- **codesPerRev** – The counts per revolution on the encoder

`CANJaguar.setVoltageRampRate(rampRate)`

Set the maximum voltage change rate.

When in PercentVbus or Voltage output mode, the rate at which the voltage changes can be limited to reduce current spikes. set this to 0.0 to disable rate limiting.

**Parameters rampRate** – The maximum rate of voltage change in Percent Voltage mode in V/s.

`CANJaguar.setupPeriodicStatus()`

Enables periodic status updates from the Jaguar

`CANJaguar.stopMotor()`

Common interface for stopping a motor.

`CANJaguar.updatePeriodicStatus()`

Check for new periodic status updates and unpack them into local variables.

**static** `CANJaguar.updateSyncGroup(syncGroup)`

Update all the motors that have pending sets in the syncGroup.

**Parameters syncGroup** – A bitmask of groups to generate synchronous output.

`CANJaguar.verify()`

Check all unverified params and make sure they're equal to their local cached versions. If a value isn't available, it gets requested. If a value doesn't match up, it gets set again.

## 1.4.16 CANTalon

**class** `wpiplib.CANTalon(deviceNumber, controlPeriodMs=None, enablePeriodMs=None)`

Bases: `wpiplib.LiveWindowSendable, wpiplib.MotorSafety`

Talon SRX device as a CAN device

The TALON SRX is designed to instrument all runtime signals periodically. The default periods are chosen to support 16 TALONs with 10ms update rate for control (throttle or setpoint). However these can be overridden with `setStatusFrameRate()`.

Likewise most control signals are sent periodically using the fire-and-forget CAN API.

Signals that are not available in an unsolicited fashion are the Close Loop gains. For teams that have a single profile for their TALON close loop they can use either the webpage to configure their TALONs once or set the `PIDF, Izone, CloseLoopRampRate, etc...` once in the robot application. These parameters are saved to flash so once they are loaded in the TALON, they will persist through power cycles and mode changes.

For teams that have one or two profiles to switch between, they can use the same strategy since there are two slots to choose from and the `ProfileSlotSelect` is periodically sent in the 10 ms control frame.



For teams that require changing gains frequently, they can use the soliciting API to get and set those parameters. Most likely they will only need to set them in a periodic fashion as a function of what motion the application is attempting. If this API is used, be mindful of the CAN utilization reported in the driver station.

If calling application has used the config routines to configure the selected feedback sensor, then all positions are measured in floating point precision rotations. All sensor velocities are specified in floating point precision RPM.

HOWEVER, if calling application has not called the config routine for selected feedback sensor, then all getters/setters for position/velocity use the native engineering units of the Talon SRX firm (just like in 2015). Signals explained below.

Encoder position is measured in encoder edges. Every edge is counted (similar to roboRIO 4X mode). Analog position is 10 bits, meaning 1024 ticks per rotation (0V => 3.3V). Use `setFeedbackDevice()` to select which sensor type you need. Once you do that you can use `getSensorPosition()` and `getSensorVelocity()`. These signals are updated on CANBus every 20ms (by default). If a relative sensor is selected, you can zero (or change the current value) using `setSensorPosition()`.

Analog Input and quadrature position (and velocity) are also explicitly reported in `getEncPosition()`, `getEncVelocity()`, `getAnalogInPosition()`, `getAnalogInRaw()`, `getAnalogInVelocity()`. These signals are available all the time, regardless of what sensor is selected at a rate of 100ms. This allows easy instrumentation for “in the pits” checking of all sensors regardless of modeselect. The 100ms rate is overridable for teams who want to acquire sensor data for processing, not just instrumentation. Or just select the sensor using `setFeedbackDevice()` to get it at 20ms.

Velocity is in position ticks / 100ms.

All output units are in respect to duty cycle (throttle) which is -1023(full reverse) to +1023 (full forward). This includes demand (which specifies duty cycle when in duty cycle mode) and `rampRamp`, which is in throttle units per 10ms (if nonzero).

When in (default) PercentVBus mode, `set()` and `get()` are automatically scaled to a -1.0 to +1.0 range to match other motor controllers.

Pos and velocity close loops are calc'd as:

```
err = target - posOrVel
iErr += err
if IZone != 0 and abs(err) > IZone:
    ClearIaccum()
output = P * err + I * iErr + D * dErr + F * target
dErr = err - lastErr
```

P, I, and D gains are always positive. F can be negative.

Motor direction can be reversed using `reverseOutput()` if sensor and motor are out of phase. Similarly feedback sensor can also be reversed (multiplied by -1) using `reverseSensor()` if you prefer the sensor to be inverted.

P gain is specified in throttle per error tick. For example, a value of 102 is ~9.9% (which is 102/1023) throttle per 1 ADC unit(10bit) or 1 quadrature encoder edge depending on selected sensor.

I gain is specified in throttle per integrated error. For example, a value of 10 equates to ~0.99% (which is 10/1023) for each accumulated ADC unit(10bit) or 1 quadrature encoder edge depending on selected sensor. Close loop and integral accumulator runs every 1ms.

D gain is specified in throttle per derivative error. For example a value of 102 equates to ~9.9% (which is 102/1023) per change of 1 unit (ADC or encoder) per ms.

I Zone is specified in the same units as sensor position (ADC units or quadrature edges). If pos/vel error is outside of this value, the integrated error will auto-clear:

```
if IZone != 0 and abs(err) > IZone:  
    ClearIaccum()
```

This is very useful in preventing integral windup and is highly recommended if using full PID to keep stability low.

CloseLoopRampRate is in throttle units per 1ms. Set to zero to disable ramping. Works the same as RampThrottle but only is in effect when a close loop mode and profile slot is selected.

**class ControlMode**

Bases: object

**Current = 3**

**Disabled = 15**

**Follower = 5**

**MotionProfile = 6**

**PercentVbus = 0**

**Position = 1**

**Speed = 2**

**Voltage = 4**

**class CANTalon.FeedbackDevice**

Bases: object

**AnalogEncoder = 3**

**AnalogPot = 2**

**CtreMagEncoder\_Absolute = 7**

**CtreMagEncoder\_Relative = 6**

**EncFalling = 5**

**EncRising = 4**

**PulseWidth = 8**

**QuadEncoder = 0**

**class CANTalon.FeedbackDeviceStatus**

Bases: object

**NotPresent = 2**

**Present = 1**

**Unknown = 0**

**class CANTalon.MotionProfileStatus**

Bases: object

This is simply a data transfer object

**activePoint = None**

(*TrajectoryPoint*) The number of points in the low level Talon buffer.

**activePointValid**

(bool) True if the active trajectory point has not empty, false otherwise. The members in activePoint are only valid if this signal is set.

**btmBufferCnt = 0**

(int) The number of points in the low level Talon buffer.

**hasUnderrun**

(bool) Set if `isUnderrun` ever gets set. Only is cleared by `clearMotionProfileHasUnderrun()` to ensure robot logic can react or instrument it.

**See also:**

`clearMotionProfileHasUnderrun()`

**isUnderrun**

(bool) This is set if Talon needs to shift a point from its buffer into the active trajectory point however the buffer is empty. This gets cleared automatically when is resolved.

**outputEnable = 0**

(SetValueMotionProfile) The current output mode of the motion profile executer (disabled, enabled, or hold). When changing the `set()` value in MP mode, it's important to check this signal to confirm the change takes effect before interacting with the top buffer.

**topBufferCnt = 0**

(int) The number of points in the top trajectory buffer.

**topBufferRem = 0**

(int) The available empty slots in the trajectory buffer.

The robot API holds a “top buffer” of trajectory points, so your applicaion can dump several points at once. The API will then stream them into the Talon’s low-level buffer, allowing the Talon to act on them.

**class** `CANTalon.PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement = 0****kRate = 1****class** `CANTalon.SetValueMotionProfile`

Bases: `object`

Enumerated types for Motion Control Set Values.

When in Motion Profile control mode, these constants are pased into `set()` to manipulate the motion profile executer.

When changing modes, be sure to read the value back using `getMotionProfileStatus()` to ensure changes in output take effect before performing buffering actions.

Disable will signal Talon to put motor output into neutral drive.

Talon will stop processing motion profile points. This means the buffer is effectively disconnected from the executer, allowing the robot to gracefully clear and push new traj points. `isUnderrun` will get cleared. The active trajectory is also cleared.

Enable will signal Talon to pop a trajectory point from it’s buffer and process it. If the active trajectory is empty, Talon will shift in the next point. If the active traj is empty, and so is the buffer, the motor drive is neutral and `isUnderrun` is set. When active traj times out, and buffer has at least one point, Talon shifts in next one, and `isUnderrun` is cleared. When active traj times out, and buffer is empty, Talon keeps processing active traj and sets `IsUnderrun`.

Hold will signal Talon keep processing the active trajectory indefinitely. If the active traj is cleared, Talon will neutral motor drive. Otherwise Talon will keep processing the active traj but it will not shift in points from the buffer. This means the buffer is effectively disconnected from the executer, allowing the robot to gracefully clear and push new traj points. `isUnderrun` is set if active traj is empty, otherwise it is cleared. `isLast` signal is also cleared.

Typical workflow:

- `set(Disable)`,
- Confirm Disable takes effect,
- clear buffer and push buffer points,
- `set(Enable)` when enough points have been pushed to ensure no underruns,
- wait for MP to finish or decide abort,
- If MP finished gracefully `set(Hold)` to hold position servo and disconnect buffer,
- If MP is being aborted `set(Disable)` to neutral the motor and disconnect buffer,
- Confirm mode takes effect,
- clear buffer and push buffer points, and rinse-repeat.

**Disable = 0**

**Enable = 1**

**Hold = 2**

**class** `CANTalon.StatusFrameRate`

Bases: `object`

enumerated types for frame rate ms

**AnalogTempVbat = 3**

**Feedback = 1**

**General = 0**

**PulseWidth = 4**

**QuadEncoder = 2**

**class** `CANTalon.TrajectoryPoint`

Bases: `object`

This is a data transfer object

**isLastPoint = False**

(bool) Set to true to signal Talon that this is the final point, so do not attempt to pop another trajectory point from out of the Talon buffer. Instead continue processing this way point. Typically the velocity member variable should be zero so that the motor doesn't spin indefinitely.

**position = 0**

(double) the position to servo to

**profileSlotSelect = 0**

(int) Which slot to get PIDF gains. PID is used for position servo. F is used as the Kv constant for velocity feed-forward. Typically this is hardcoded to the a particular slot, but you are free gain schedule if need be.

**timeDurMs = 0**

(int) Time in milliseconds to process this point. Value should be between 1ms and 255ms. If value is zero then Talon will default to 1ms. If value exceeds 255ms API will cap it.

**velocity = 0**

(double) The velocity to feed-forward

**velocityOnly = False**

Set to true to only perform the velocity feed-forward and not perform position servo. This is useful when learning how the position servo changes the motor response. The same could be accomplished by clearing the PID gains, however this is synchronous to the streaming, and doesn't require restoring gains when finished.

Additionally setting this basically gives you direct control of the motor output since motor output = targetVelocity X Kv, where Kv is our Fgain. This means you can also schedule straight-throttle curves without relying on a sensor.

**zeroPos = False**

(bool) Set to true to signal Talon to zero the selected sensor. When generating MPs, one simple method is to make the first target position zero, and the final target position the target distance from the current position. Then when you fire the MP, the current position gets set to zero. If this is the intent, you can set zeroPos on the first trajectory point.

Otherwise you can leave this false for all points, and offset the positions of all trajectory points so they are correct.

CANTalon.**changeControlMode** (*controlMode*)

CANTalon.**changeMotionControlFramePeriod** (*periodMs*)

Calling application can opt to speed up the handshaking between the robot API and the Talon to increase the download rate of the Talon's Motion Profile. Ideally the period should be no more than half the period of a trajectory point.

CANTalon.**clearIaccum** ()

Clear the accumulator for I gain.

CANTalon.**clearMotionProfileHasUnderrun** ()

Clear the hasUnderrun flag in Talon's Motion Profile Executer when MPE is ready for another point, but the low level buffer is empty.

Once the Motion Profile Executer sets the hasUnderrun flag, it stays set until Robot Application clears it with this routine, which ensures Robot Application gets a chance to instrument or react. Caller could also check the isUnderrun flag which automatically clears when fault condition is removed.

CANTalon.**clearMotionProfileTrajectories** ()

Clear the buffered motion profile in both Talon RAM (bottom), and in the API (top). Be sure to check [getMotionProfileStatus\(\)](#) to know when the buffer is actually cleared.

CANTalon.**clearStickyFaults** ()

CANTalon.**configEncoderCodesPerRev** (*codesPerRev*)

Configure how many codes per revolution are generated by your encoder.

**Parameters** *codesPerRev* – The number of counts per revolution.

CANTalon.**configFwdLimitSwitchNormallyOpen** (*normallyOpen*)

Configure the fwd limit switch to be normally open or normally closed. Talon will disable momentarily if the Talon's current setting is dissimilar to the caller's requested setting.

Since Talon saves setting to flash this should only affect a given Talon initially during robot install.

**Parameters** *normallyOpen* – True for normally open. False for normally closed.

`CANTalon.configMaxOutputVoltage` (*voltage*)

Configure the maximum voltage that the Jaguar will ever output.

This can be used to limit the maximum output voltage in all modes so that motors which cannot withstand full bus voltage can be used safely.

**Parameters** `voltage` – The maximum voltage output by the Jaguar.

`CANTalon.configNominalOutputVoltage` (*forwardVoltage, reverseVoltage*)

`CANTalon.configPeakOutputVoltage` (*forwardVoltage, reverseVoltage*)

`CANTalon.configPotentiometerTurns` (*turns*)

Configure the number of turns on the potentiometer.

**Parameters** `turns` – The number of turns of the potentiometer.

`CANTalon.configRevLimitSwitchNormallyOpen` (*normallyOpen*)

- Configure the rev limit switch to be normally open or normally closed.
- Talon will disable momentarily if the Talon's current setting
- is dissimilar to the caller's requested setting.
- 
- Since Talon saves setting to flash this should only affect
- a given Talon initially during robot install.
- 
- @param normallyOpen true for normally open. false for normally closed.

`CANTalon.disable` ()

`CANTalon.disableControl` ()

`CANTalon.enable` ()

`CANTalon.enableBrakeMode` (*brake*)

`CANTalon.enableControl` ()

`CANTalon.enableForwardSoftLimit` (*enable*)

`CANTalon.enableLimitSwitch` (*forward, reverse*)

`CANTalon.enableReverseSoftLimit` (*enable*)

`CANTalon.enableZeroSensorPositionOnIndex` (*enable, risingEdge*)

Enables Talon SRX to automatically zero the Sensor Position whenever an edge is detected on the index signal.

**Parameters**

- `enable` (*boolean*) – boolean input, pass true to enable feature or false to disable.
- `risingEdge` (*boolean*) – boolean input, pass true to clear the position on rising edge, pass false to clear the position on falling edge.

`CANTalon.free` ()

`CANTalon.get` ()

Gets the current status of the Talon (usually a sensor value).

In Current mode: returns output current.

In Speed mode: returns current speed.

In Position mode: returns current sensor position.

In Throttle and Follower modes: returns current applied throttle.

**Returns** The current sensor value of the Talon.

`CANTalon.getAnalogInPosition()`

Get the current analog in position, regardless of whether it is the current feedback device.

**Returns** The 24bit analog position. The bottom ten bits is the ADC (0 - 1023) on the analog pin of the Talon. The upper 14 bits tracks the overflows and underflows (continuous sensor).

`CANTalon.getAnalogInRaw()`

Get the current analog in position, regardless of whether it is the current feedback device. :returns: The ADC (0 - 1023) on analog pin of the Talon.

`CANTalon.getAnalogInVelocity()`

Get the current encoder velocity, regardless of whether it is the current feedback device.

**Returns** The current speed of the analog in device.

`CANTalon.getBrakeEnabledDuringNeutral()`

Returns True if break is enabled during neutral. False if coast.

`CANTalon.getBusVoltage()`

**Returns** The voltage at the battery terminals of the Talon, in Volts.

`CANTalon.getCloseLoopRampRate()`

Get the closed loop ramp rate for the current profile.

Limits the rate at which the throttle will change. Only affects position and speed closed loop modes.

**Returns** rampRate Maximum change in voltage, in volts / sec.

**See** #setProfile For selecting a certain profile.

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getClosedLoopError()`

Get the current difference between the setpoint and the sensor value.

**Returns** The error, in whatever units are appropriate.

`CANTalon.getControlMode()`

`CANTalon.getD()`

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getDescription()`

`CANTalon.getDeviceID()`

`CANTalon.getEncPosition()`

Get the current encoder position, regardless of whether it is the current feedback device.

**Returns** The current position of the encoder.

`CANTalon.getEncVelocity()`

Get the current encoder velocity, regardless of whether it is the current feedback device.

**Returns** The current speed of the encoder.

`CANTalon.getError()`

Returns the difference between the setpoint and the current position.

**Returns** The error in units corresponding to whichever mode we are in.

**See also:**

`set()` for a detailed description of the various units.

`CANTalon.getF()`

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getFaultForLim()`

`CANTalon.getFaultForSoftLim()`

`CANTalon.getFaultHardwareFailure()`

`CANTalon.getFaultOverTemp()`

`CANTalon.getFaultRevLim()`

`CANTalon.getFaultRevSoftLim()`

`CANTalon.getFaultUnderVoltage()`

`CANTalon.getFirmwareVersion()`

**Returns** The version of the firmware running on the Talon

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getForwardSoftLimit()`

`CANTalon.getI()`

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getIZone()`

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getIaccum()`

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getInverted()`

Common interface for the inverting direction of a speed controller.

**Returns** The state of inversion (True is inverted).

`CANTalon.getMotionProfileStatus()` (*motionProfileStatus*)

Retrieve all Motion Profile status information.

Since this all comes from one CAN frame, its ideal to have one routine to retrieve the frame once and decode everything.

**Parameters** `motionProfileStatus` (*MotionProfileStatus*) – contains all progress information on the currently running MP. Caller should must instantiate the `motionProfileStatus` object first then pass into this routine to be filled.



`CANTalon.getMotionProfileTopLevelBufferCount ()`

Retrieve just the buffer count for the api-level (top) buffer. This routine performs no CAN or data structure lookups, so its fast and ideal if caller needs to quickly poll the progress of trajectory points being emptied into Talon's RAM. Otherwise just use `getMotionProfileStatus ()`.

**Returns** number of trajectory points in the top buffer.

`CANTalon.getNumberOfQuadIdxRises ()`

Get the number of of rising edges seen on the index pin.

**Returns** number of rising edges on idx pin.

`CANTalon.getOutputCurrent ()`

Returns the current going through the Talon, in Amperes.

`CANTalon.getOutputVoltage ()`

**Returns** The voltage being output by the Talon, in Volts.

`CANTalon.getP ()`

Get the current proportional constant.

**Returns** double proportional constant for current profile.

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getPIDSourceType ()`

`CANTalon.getParameter (param)`

General get frame. Since the parameter is a general integral type, this can be used for testing future features.

**Warning:** Calls `Timer.delay(kDelayForSolicitedSignals)`

`CANTalon.getPinStateQuadA ()`

**Returns** IO level of QUADA pin.

`CANTalon.getPinStateQuadB ()`

**Returns** IO level of QUADB pin.

`CANTalon.getPinStateQuadIdx ()`

**Returns** IO level of QUAD Index pin.

`CANTalon.getPosition ()`

**Returns** The position of the sensor currently providing feedback. When using analog sensors, 0 units corresponds to 0V, 1023 units corresponds to 3.3V When using an analog encoder (wrapping around 1023 to 0 is possible) the units are still 3.3V per 1023 units. When using quadrature, each unit is a quadrature edge (4X) mode.

`CANTalon.getPulseWidthPosition ()`

`CANTalon.getPulseWidthRiseToFallUs ()`

`CANTalon.getPulseWidthRiseToRiseUs ()`

`CANTalon.getPulseWidthVelocity ()`

`CANTalon.getReverseSoftLimit ()`

`CANTalon.getSetpoint ()`

**Returns** The latest value set using set().

`CANTalon.getSpeed()`

**Returns** The speed of the sensor currently providing feedback.

The speed units will be in the sensor's native ticks per 100ms.

For analog sensors, 3.3V corresponds to 1023 units. So a speed of 200 equates to ~0.645 dV per 100ms or 6.451 dV per second. If this is an analog encoder, that likely means 1.9548 rotations per sec. For quadrature encoders, each unit corresponds a quadrature edge (4X). So a 250 count encoder will produce 1000 edge events per rotation. An example speed of 200 would then equate to 20% of a rotation per 100ms, or 10 rotations per second.

`CANTalon.getStickyFaultForLim()`

`CANTalon.getStickyFaultForSoftLim()`

`CANTalon.getStickyFaultOverTemp()`

`CANTalon.getStickyFaultRevLim()`

`CANTalon.getStickyFaultRevSoftLim()`

`CANTalon.getStickyFaultUnderVoltage()`

`CANTalon.getTemp()`

Returns temperature of Talon, in degrees Celsius.

`CANTalon.getTemperature()`

Returns temperature of Talon, in degrees Celsius.

`CANTalon.handle`

`CANTalon.isControlEnabled()`

`CANTalon.isEnabled()`

Return true if Talon is enabled.

**Returns** true if the Talon is enabled and may be applying power to the motor

`CANTalon.isForwardSoftLimitEnabled()`

`CANTalon.isFwdLimitSwitchClosed()`

Returns True if limit switch is closed. False if open.

`CANTalon.isMotionProfileTopLevelBufferFull()`

**Returns** true if api-level (top) buffer is full.

`CANTalon.isRevLimitSwitchClosed()`

Returns True if limit switch is closed. False if open.

`CANTalon.isReverseSoftLimitEnabled()`

`CANTalon.isSensorPresent(feedbackDevice)`

**Parameters** `feedbackDevice` – which feedback sensor to check it if is connected.

**Returns** status of caller's specified sensor type.

`CANTalon.kDelayForSolicitedSignals = 0.004`

`CANTalon.kMinutesPer100msUnit = 0.0016666666666666668`

Number of minutes per 100ms unit. Useful for scaling velocities measured by Talon's 100ms timebase to rotations per minute.

`CANTalon.kNativeAdcUnitsPerRotation = 1024`

Number of adc engineering units per 0 to 3.3V sweep. This is necessary for scaling Analog Position in rotations/RPM.

`CANTalon.kNativePwUnitsPerRotation = 4096.0`

Number of pulse width engineering units per full rotation. This is necessary for scaling Pulse Width Decoded Position in rotations/RPM.

`CANTalon.pidGet ()`

`CANTalon.pidWrite (output)`

`CANTalon.processMotionProfileBuffer ()`

This must be called periodically to funnel the trajectory points from the API's top level buffer to the Talon's bottom level buffer. Recommendation is to call this twice as fast as the execution rate of the motion profile. So if MP is running with 20ms trajectory points, try calling this routine every 10ms. All motion profile functions are thread-safe through the use of a mutex, so there is no harm in having the caller utilize threading.

`CANTalon.pushMotionProfileTrajectory (trajPt)`

Push another trajectory point into the top level buffer (which is emptied into the Talon's bottom buffer as room allows).

#### Parameters

- **targPos** – servo position in native Talon units (sensor units).
- **targVel** – velocity to feed-forward in native Talon units (sensor units per 100ms).
- **profileSlotSelect** – which slot to pull PIDF gains from. Currently supports 0 or 1.
- **timeDurMs** – time in milliseconds of how long to apply this point.
- **velOnly** – set to nonzero to signal Talon that only the feed-forward velocity should be used, i.e. do not perform PID on position. This is equivalent to setting PID gains to zero, but much more efficient and synchronized to MP.
- **isLastPoint** – set to nonzero to signal Talon to keep processing this trajectory point, instead of jumping to the next one when timeDurMs expires. Otherwise MP executer will eventually see an empty buffer after the last point expires, causing it to assert the IsUnderRun flag. However this may be desired if calling application never wants to terminate the MP.
- **zeroPos** – set to nonzero to signal Talon to “zero” the selected position sensor before executing this trajectory point. Typically the first point should have this set only thus allowing the remainder of the MP positions to be relative to zero.

**Returns** True if trajectory point push ok. False if buffer is full due to kMotionProfileTopBuffer-Capacity.

`CANTalon.reset ()`

Resets the accumulated integral error and disables the controller.

The only difference between this and `{@link PIDController#reset}` is that the `PIDController` also resets the previous error for the D term, but the difference should have minimal effect as it will only last one cycle.

`CANTalon.reverseOutput (flip)`

Flips the sign (multiplies by negative one) the throttle values going into the motor on the talon in closed loop modes.

**Parameters** **flip** – True if motor output should be flipped; False if not.

`CANTalon.reverseSensor` (*flip*)

Flips the sign (multiplies by negative one) the sensor values going into the talon.

**This only affects position and velocity closed loop control. Allows for** situations where you may have a sensor flipped and going in the wrong direction.

**Parameters** `flip` – True if sensor input should be flipped; False if not.

`CANTalon.set` (*outputValue*, *syncGroup=0*)

Sets the appropriate output on the talon, depending on the mode.

In PercentVbus, the output is between -1.0 and 1.0, with 0.0 as stopped.

**In Follower mode, the output is the integer device ID of the talon to** duplicate.

In Voltage mode, `outputValue` is in volts.

In Current mode, `outputValue` is in amperes.

In Speed mode, `outputValue` is in position change / 10ms.

**In Position mode, outputValue is in encoder ticks or an analog value,** depending on the sensor.

**Parameters** `outputValue` – The setpoint value, as described above.

`CANTalon.setAllowableClosedLoopErr` (*allowableCloseLoopError*)

Set the allowable closed loop error.

**Parameters** `allowableCloseLoopError` – allowable closed loop error for selected profile. mA for Curent closed loop. Talon Native Units for position and velocity.

`CANTalon.setAnalogPosition` (*newPosition*)

`CANTalon.setCloseLoopRampRate` (*rampRate*)

Set the closed loop ramp rate for the current profile.

Limits the rate at which the throttle will change. Only affects position and speed closed loop modes.

**Parameters** `rampRate` – Maximum change in voltage, in volts / sec.

**See** `setProfile()` For selecting a certain profile.

`CANTalon.setControlMode` (*controlMode*)

`CANTalon.setD` (*d*)

Set the derivative constant of the currently selected profile.

**Parameters** `d` – Derivative constant for the currently selected PID profile.

**See** `setProfile()` For selecting a certain profile.

`CANTalon.setEncPosition` (*newPosition*)

`CANTalon.setF` (*f*)

Set the feedforward value of the currently selected profile.

**Parameters** `f` – Feedforward constant for the currently selected PID profile.

**See** `setProfile()` For selecting a certain profile.

`CANTalon.setFeedbackDevice` (*device*)

`CANTalon.setForwardSoftLimit` (*forwardLimit*)

`CANTalon.setI` (*i*)

Set the integration constant of the currently selected profile.

**Parameters** **i** – Integration constant for the currently selected PID profile.

See `setProfile()` For selecting a certain profile.

`CANTalon.setIZone(izone)`

Set the integration zone of the current Closed Loop profile.

Whenever the error is larger than the `izone` value, the accumulated integration error is cleared so that high errors aren't racked up when at high errors.

An `izone` value of 0 means no difference from a standard PIDF loop.

**Parameters** **izone** – Width of the integration zone.

See `setProfile()` For selecting a certain profile.

`CANTalon.setInverted(isInverted)`

Inverts the direction of the motor's rotation. Only works in PercentVbus mode.

**Parameters** **isInverted** – The state of inversion (True is inverted).

`CANTalon.setP(p)`

Set the proportional value of the currently selected profile.

**Parameters** **p** – Proportional constant for the currently selected PID profile.

See `setProfile()` For selecting a certain profile.

`CANTalon.setPID(p, i, d, f=0, izone=0, closeLoopRampRate=0, profile=None)`

Sets control values for closed loop control.

**Parameters**

- **p** – Proportional constant.
- **i** – Integration constant.
- **d** – Differential constant.
- **f** – Feedforward constant.
- **izone** – Integration zone – prevents accumulation of integration error with large errors. Setting this to zero will ignore any `izone` stuff.
- **closeLoopRampRate** – Closed loop ramp rate. Maximum change in voltage, in volts / sec.
- **profile** – which profile to set the pid constants for. You can have two profiles, with values of 0 or 1, allowing you to keep a second set of values on hand in the talon. In order to switch profiles without recalling `setPID`, you must call `setProfile()`.

`CANTalon.setPIDSourceType(pidSource)`

`CANTalon.setParameter(param, value)`

General set frame. Since the parameter is a general integral type, this can be used for testing future features.

`CANTalon.setPosition(pos)`

`CANTalon.setProfile(profile)`

Select which closed loop profile to use, and uses whatever PIDF gains and the such that are already there.

**Parameters** **profile** (*int*) – Selected profile (0 or 1)

`CANTalon.setPulseWidthPosition(newPosition)`

`CANTalon.setReverseSoftLimit(reverseLimit)`

`CANTalon.setSetpoint (setpoint)`

Calls `set ()`

`CANTalon.setStatusFrameRateMs (stateFrame, periodMs)`

Change the periodMs of a TALON's status frame. See `StatusFrameRate` enum for what's available.

`CANTalon.setVoltageCompensationRampRate (rampRate)`

`CANTalon.setVoltageRampRate (rampRate)`

Set the voltage ramp rate for the current profile.

Limits the rate at which the throttle will change. Affects all modes.

**Parameters** `rampRate` – Maximum change in voltage, in volts / sec.

`CANTalon.stopMotor ()`

Common interface for stopping a motor.

## 1.4.17 Compressor

`class wpilib.Compressor (pcmId=None)`

Bases: `wpilib.SensorBase`

Operates the PCM (Pneumatics compressor module)

The PCM automatically will run in close-loop mode by default whenever a Solenoid object is created. For most cases the Compressor object does not need to be instantiated or used in a robot program.

This class is only required in cases where more detailed status or to enable/disable closed loop control. Note: you cannot operate the compressor directly from this class as doing so would circumvent the safety provided in using the pressure switch and closed loop control. You can only turn off closed loop control, thereby stopping the compressor from operating.

Create an instance of the Compressor

**Parameters** `pcmID` – The PCM CAN device ID. Most robots that use PCM will have a single module. Use this for supporting a second module other than the default.

`clearAllPCMStickyFaults ()`

`enabled ()`

Get the enabled status of the compressor.

**Returns** True if the compressor is on

**Return type** bool

`getClosedLoopControl ()`

Gets the current operating mode of the PCM.

**Returns** True if compressor is operating on closed-loop mode, otherwise return False.

**Return type** bool

`getCompressorCurrent ()`

Get the current being used by the compressor.

**Returns** Current consumed in amps for the compressor motor

**Return type** float

`getCompressorCurrentTooHighFault ()`

**Returns** True if PCM is in fault state : Compressor Drive is disabled due to compressor current being too high

**getCompressorCurrentTooHighStickyFault** ()

**Returns** True if PCM sticky fault is set : Compressor Drive is disabled due to compressor current being too high

**getCompressorNotConnectedFault** ()

**Returns** True if PCM is in fault state : Compressor does not appear to be wired, i.e. compressor is not drawing enough current.

**getCompressorNotConnectedStickyFault** ()

**Returns** True if PCM sticky fault is set : Compressor does not appear to be wired, i.e. compressor is not drawing enough current.

**getCompressorShortedFault** ()

**Returns** True if PCM is in fault state : Compressor Output appears to be shorted

**getCompressorShortedStickyFault** ()

**Returns** True if PCM sticky fault is set : Compressor Output appears to be shorted

**getPressureSwitchValue** ()

Get the current pressure switch value.

**Returns** True if the pressure is low by reading the pressure switch that is plugged into the PCM

**Return type** bool

**setClosedLoopControl** (*on*)

Set the PCM in closed loop control mode.

**Parameters** *on* (*bool*) – If True sets the compressor to be in closed loop control mode otherwise normal operation of the compressor is disabled.

**start** ()

Start the compressor running in closed loop control mode. Use the method in cases where you would like to manually stop and start the compressor for applications such as conserving battery or making sure that the compressor motor doesn't start during critical operations.

**stop** ()

Stop the compressor from running in closed loop control mode. Use the method in cases where you would like to manually stop and start the compressor for applications such as conserving battery or making sure that the compressor motor doesn't start during critical operations.

## 1.4.18 ControllerPower

**class** `wpiplib.ControllerPower`

Bases: `object`

Provides access to power levels on the RoboRIO

**static** `getCurrent3V3` ()

Get the current output of the 3.3V rail

**Returns** The controller 3.3V rail output current value in Amps

**Return type** float

**static** `getCurrent5V` ()

Get the current output of the 5V rail

**Returns** The controller 5V rail output current value in Amps

**Return type** float

**static** `getCurrent6V()`

Get the current output of the 6V rail

**Returns** The controller 6V rail output current value in Amps

**Return type** float

**static** `getEnabled3V3()`

Get the enabled state of the 3.3V rail. The rail may be disabled due to a controller brownout, a short circuit on the rail, or controller over-voltage

**Returns** True if enabled, False otherwise

**Return type** bool

**static** `getEnabled5V()`

Get the enabled state of the 5V rail. The rail may be disabled due to a controller brownout, a short circuit on the rail, or controller over-voltage

**Returns** True if enabled, False otherwise

**Return type** bool

**static** `getEnabled6V()`

Get the enabled state of the 6V rail. The rail may be disabled due to a controller brownout, a short circuit on the rail, or controller over-voltage

**Returns** True if enabled, False otherwise

**Return type** bool

**static** `getFaultCount3V3()`

Get the count of the total current faults on the 3.3V rail since the controller has booted

**Returns** The number of faults

**Return type** int

**static** `getFaultCount5V()`

Get the count of the total current faults on the 5V rail since the controller has booted

**Returns** The number of faults

**Return type** int

**static** `getFaultCount6V()`

Get the count of the total current faults on the 6V rail since the controller has booted

**Returns** The number of faults

**Return type** int

**static** `getInputCurrent()`

Get the input current to the robot controller

**Returns** The controller input current value in Amps

**Return type** float

**static** `getInputVoltage()`

Get the input voltage to the robot controller

**Returns** The controller input voltage value in Volts

**Return type** float



**static** `getVoltage3V3()`

Get the voltage of the 3.3V rail

**Returns** The controller 3.3V rail voltage value in Volts

**Return type** float

**static** `getVoltage5V()`

Get the voltage of the 5V rail

**Returns** The controller 5V rail voltage value in Volts

**Return type** float

**static** `getVoltage6V()`

Get the voltage of the 6V rail

**Returns** The controller 6V rail voltage value in Volts

**Return type** float

### 1.4.19 Counter

**class** `wpiplib.Counter` (\*args, \*\*kwargs)

Bases: `wpiplib.SensorBase`

Counts the number of ticks on a *DigitalInput* channel.

This is a general purpose class for counting repetitive events. It can return the number of counts, the period of the most recent cycle, and detect when the signal being counted has stopped by supplying a maximum cycle time.

All counters will immediately start counting - `reset()` them if you need them to be zeroed before use.

Counter constructor.

The counter will start counting immediately.

Positional arguments may be either channel numbers, *DigitalSource* sources, or *AnalogTrigger* sources in the following order:

A “source” is any valid single-argument input to `setUpSource()` and `setDownSource()`

- (none)
- upSource
- upSource, down source

And, to keep consistency with Java wpiplib. - `encodingType`, up source, down source, inverted

If the passed object has a `getChannelForRouting` function, it is assumed to be a *DigitalSource*. If the passed object has a `createOutput` function, it is assumed to be an *AnalogTrigger*.

In addition, extra keyword parameters may be provided for mode, inverted, and `encodingType`.

#### Parameters

- **upSource** – The source (channel num, *DigitalInput*, or *AnalogTrigger*) that should be used for up counting.
- **downSource** – The source (channel num, *DigitalInput*, or *AnalogTrigger*) that should be used for down counting or direction control.
- **mode** – How and what the counter counts (see *Mode*). Defaults to *Mode.kTwoPulse* for zero or one source, and *Mode.kExternalDirection* for two sources.

- **inverted** – Flips the direction of counting. Defaults to False if unspecified. Only used when two sources are specified.
- **encodingType** (*Counter.EncodingType*) – Either k1X or k2X to indicate 1X or 2X decoding. 4X decoding is not supported by Counter; use *Encoder* instead. Defaults to k1X if unspecified. Only used when two sources are specified.

**class EncodingType**

Bases: object

The number of edges for the counterbase to increment or decrement on

**k1X = 0**

**k2X = 1**

**k4X = 2**

**class Counter.Mode**

Bases: object

Mode determines how and what the counter counts

**kExternalDirection = 3**

external direction mode

**kPulseLength = 2**

pulse length mode

**kSemiperiod = 1**

semi period mode

**kTwoPulse = 0**

two pulse mode

**class Counter.PIDSourceType**

Bases: object

A description for the type of output value to provide to a *PIDController*

**kDisplacement = 0**

**kRate = 1**

`Counter.allocatedDownSource = False`

`Counter.allocatedUpSource = False`

`Counter.clearDownSource ()`

Disable the down counting source to the counter.

`Counter.clearUpSource ()`

Disable the up counting source to the counter.

`Counter.counter`

`Counter.free ()`

`Counter.get ()`

Read the current counter value. Read the value at this instant. It may still be running, so it reflects the current value. Next time it is read, it might have a different value.

`Counter.getDirection ()`

The last direction the counter value changed.

**Returns** The last direction the counter value changed.

**Return type** bool

`Counter.getDistance()`

Read the current scaled counter value. Read the value at this instant, scaled by the distance per pulse (defaults to 1).

**Returns** Scaled value

**Return type** float

`Counter.getFPGAIndex()`

**Returns** The Counter's FPGA index.

`Counter.getPIDSourceType()`

`Counter.getPeriod()`

Get the Period of the most recent count. Returns the time interval of the most recent count. This can be used for velocity calculations to determine shaft speed.

**Returns** The period of the last two pulses in units of seconds.

**Return type** float

`Counter.getRate()`

Get the current rate of the Counter. Read the current rate of the counter accounting for the distance per pulse value. The default value for distance per pulse (1) yields units of pulses per second.

**Returns** The rate in units/sec

**Return type** float

`Counter.getSamplesToAverage()`

Get the Samples to Average which specifies the number of samples of the timer to average when calculating the period. Perform averaging to account for mechanical imperfections or as oversampling to increase resolution.

**Returns** The number of samples being averaged (from 1 to 127)

**Return type** int

`Counter.getStopped()`

Determine if the clock is stopped. Determine if the clocked input is stopped based on the MaxPeriod value set using the `setMaxPeriod()` method. If the clock exceeds the MaxPeriod, then the device (and counter) are assumed to be stopped and it returns True.

**Returns** Returns True if the most recent counter period exceeds the MaxPeriod value set by SetMaxPeriod.

**Return type** bool

`Counter.pidGet()`

`Counter.reset()`

Reset the Counter to zero. Set the counter value to zero. This doesn't effect the running state of the counter, just sets the current value to zero.

`Counter.setDistancePerPulse(distancePerPulse)`

Set the distance per pulse for this counter. This sets the multiplier used to determine the distance driven based on the count value from the encoder. Set this value based on the Pulses per Revolution and factor in any gearing reductions. This distance can be in any units you like, linear or angular.

**Parameters** `distancePerPulse` (*float*) – The scale factor that will be used to convert pulses to useful units.

`Counter.setDownSource(*args, **kwargs)`

Set the down counting source for the counter.

This function accepts either a digital channel index, a *DigitalSource*, or an *AnalogTrigger* as positional arguments:

- `source`
- `channel`
- `analogTrigger`
- `analogTrigger, triggerType`

For positional arguments, if the passed object has a *getChannelForRouting* function, it is assumed to be a *DigitalSource*. If the passed object has a *createOutput* function, it is assumed to be an *AnalogTrigger*.

Alternatively, sources and/or channels may be passed as keyword arguments. The behavior of specifying both a source and a number for the same channel is undefined, as is passing both a positional and a keyword argument for the same channel.

#### Parameters

- **channel** (*int*) – the DIO channel to use as the down source. 0-9 are on-board, 10-25 are on the MXP
- **source** (*DigitalInput*) – The digital source to count
- **analogTrigger** (*AnalogTrigger*) – The analog trigger object that is used for the Up Source
- **triggerType** (*AnalogTriggerType*) – The analog trigger output that will trigger the counter. Defaults to `kState` if not specified.

`Counter.setDownSourceEdge(risingEdge, fallingEdge)`

Set the edge sensitivity on an down counting source. Set the down source to either detect rising edges or falling edges.

#### Parameters

- **risingEdge** (*bool*) – True to count rising edge
- **fallingEdge** (*bool*) – True to count falling edge

`Counter.setExternalDirectionMode()`

Set external direction mode on this counter. Counts are sourced on the Up counter input. The Down counter input represents the direction to count.

`Counter.setMaxPeriod(maxPeriod)`

Set the maximum period where the device is still considered “moving”. Sets the maximum period where the device is considered moving. This value is used to determine the “stopped” state of the counter using the *getStopped()* method.

**Parameters** `maxPeriod` (*float or int*) – The maximum period where the counted device is considered moving in seconds.

`Counter.setPIDSourceType(pidSource)`

Set which parameter of the encoder you are using as a process control variable. The counter class supports the rate and distance parameters.

**Parameters** `pidSource` (*Counter.PIDSourceType*) – An enum to select the parameter.

`Counter.setPulseLengthMode(threshold)`

Configure the counter to count in up or down based on the length of the input pulse. This mode is most useful for direction sensitive gear tooth sensors.

**Parameters** `threshold` (*float, int*) – The pulse length beyond which the counter counts the opposite direction. Units are seconds.

`Counter.setReverseDirection` (*reverseDirection*)

Set the Counter to return reversed sensing on the direction. This allows counters to change the direction they are counting in the case of 1X and 2X quadrature encoding only. Any other counter mode isn't supported.

**Parameters** `reverseDirection` (*bool*) – True if the value counted should be negated.

`Counter.setSamplesToAverage` (*samplesToAverage*)

Set the Samples to Average which specifies the number of samples of the timer to average when calculating the period. Perform averaging to account for mechanical imperfections or as oversampling to increase resolution.

**Parameters** `samplesToAverage` (*int*) – The number of samples to average from 1 to 127.

`Counter.setSemiPeriodMode` (*highSemiPeriod*)

Set Semi-period mode on this counter. Counts up on both rising and falling edges.

**Parameters** `highSemiPeriod` (*bool*) – True to count up on both rising and falling

`Counter.setUpDownCounterMode` ()

Set standard up / down counting mode on this counter. Up and down counts are sourced independently from two inputs.

`Counter.setUpSource` (*\*args, \*\*kwargs*)

Set the up counting source for the counter.

This function accepts either a digital channel index, a *DigitalSource*, or an *AnalogTrigger* as positional arguments:

- `source`
- `channel`
- `analogTrigger`
- `analogTrigger, triggerType`

For positional arguments, if the passed object has a *getChannelForRouting* function, it is assumed to be a *DigitalSource*. If the passed object has a *createOutput* function, it is assumed to be an *AnalogTrigger*.

Alternatively, sources and/or channels may be passed as keyword arguments. The behavior of specifying both a source and a number for the same channel is undefined, as is passing both a positional and a keyword argument for the same channel.

#### Parameters

- **channel** (*int*) – the DIO channel to use as the up source. 0-9 are on-board, 10-25 are on the MXP
- **source** (*DigitalInput*) – The digital source to count
- **analogTrigger** (*AnalogTrigger*) – The analog trigger object that is used for the Up Source
- **triggerType** (*AnalogTriggerType*) – The analog trigger output that will trigger the counter. Defaults to `kState` if not specified.

`Counter.setUpSourceEdge` (*risingEdge, fallingEdge*)

Set the edge sensitivity on an up counting source. Set the up source to either detect rising edges or falling edges.

#### Parameters

- **risingEdge** (*bool*) – True to count rising edge
- **fallingEdge** (*bool*) – True to count falling edge

**Counter.setUpdateWhenEmpty** (*enabled*)

Select whether you want to continue updating the event timer output when there are no samples captured. The output of the event timer has a buffer of periods that are averaged and posted to a register on the FPGA. When the timer detects that the event source has stopped (based on the MaxPeriod) the buffer of samples to be averaged is emptied. If you enable update when empty, you will be notified of the stopped source and the event time will report 0 samples. If you disable update when empty, the most recent average will remain on the output until a new sample is acquired. You will never see 0 samples output (except when there have been no events since an FPGA reset) and you will likely not see the stopped bit become true (since it is updated at the end of an average and there are no samples to average).

**Parameters enabled** (*bool*) – True to continue updating

## 1.4.20 DigitalGlitchFilter

**class** `wpilib.DigitalGlitchFilter`

Bases: `wpilib.SensorBase`

Class to enable glitch filtering on a set of digital inputs. This class will manage adding and removing digital inputs from a FPGA glitch filter. The filter lets the user configure the time that an input must remain high or low before it is classified as high or low.

**add** (*input*)

Assigns the *DigitalSource*, *Encoder*, or *Counter* to this glitch filter.

**Parameters input** – Object to add

**filterAllocated** = [False, False, False]

**free** ()

**getPeriodCycles** ()

Gets the number of FPGA cycles that the input must hold steady to pass through this glitch filter.

**Returns** The number of cycles.

**getPeriodNanoSeconds** ()

Gets the number of nanoseconds that the input must hold steady to pass through this glitch filter.

**Returns** The number of nanoseconds.

**mutex** = `<_thread.lock object>`

**remove** (*input*)

Removes this filter from the given input object

**setPeriodCycles** (*fpga\_cycles*)

Sets the number of FPGA cycles that the input must hold steady to pass through this glitch filter.

**Parameters fpga\_cycles** – The number of FPGA cycles.

**setPeriodNanoSeconds** (*nanoseconds*)

Sets the number of nanoseconds that the input must hold steady to pass through this glitch filter.

**Parameters nanoseconds** – The number of nanoseconds.

### 1.4.21 DigitalInput

**class** `wpiplib.DigitalInput` (*channel*)

Bases: `wpiplib.DigitalSource`

Reads a digital input.

This class will read digital inputs and return the current value on the channel. Other devices such as encoders, gear tooth sensors, etc. that are implemented elsewhere will automatically allocate digital inputs and outputs as required. This class is only for devices like switches etc. that aren't implemented anywhere else.

Create an instance of a Digital Input class. Creates a digital input given a channel.

**Parameters** `channel` (*int*) – the DIO channel for the digital input. 0-9 are on-board, 10-25 are on the MXP

**free** ()

**get** ()

Get the value from a digital input channel. Retrieve the value of a single digital input channel from the FPGA.

**Returns** the state of the digital input

**Return type** bool

**getAnalogTriggerForRouting** ()

**getChannel** ()

Get the channel of the digital input

**Returns** The GPIO channel number that this object represents.

**Return type** int

### 1.4.22 DigitalOutput

**class** `wpiplib.DigitalOutput` (*channel*)

Bases: `wpiplib.DigitalSource`

Writes to a digital output

Other devices that are implemented elsewhere will automatically allocate digital inputs and outputs as required.

Create an instance of a digital output.

**Parameters** `channel` – the DIO channel for the digital output. 0-9 are on-board, 10-25 are on the MXP

**disablePWM** ()

Change this line from a PWM output back to a static Digital Output line.

Free up one of the 6 DO PWM generator resources that were in use.

**enablePWM** (*initialDutyCycle*)

Enable a PWM Output on this line.

Allocate one of the 6 DO PWM generator resources.

Supply the initial duty-cycle to output so as to avoid a glitch when first starting.

The resolution of the duty cycle is 8-bit for low frequencies (1kHz or less) but is reduced the higher the frequency of the PWM signal is.

**Parameters** `initialDutyCycle` (*float*) – The duty-cycle to start generating. [0..1]

**free** ()

Free the resources associated with a digital output.

**getChannel** ()

**Returns** The GPIO channel number that this object represents.

**isPulsing** ()

Determine if the pulse is still going. Determine if a previously started pulse is still going.

**Returns** True if pulsing

**Return type** bool

**pulse** (*channel*, *pulseLength*)

Generate a single pulse. Write a pulse to the specified digital output channel. There can only be a single pulse going at any time.

**Parameters**

- **channel** – The channel to pulse.
- **pulseLength** (*float*) – The length of the pulse.

**pwmGenerator**

**set** (*value*)

Set the value of a digital output.

**Parameters** **value** (*bool*) – True is on, off is False

**setPWMRate** (*rate*)

Change the PWM frequency of the PWM output on a Digital Output line.

The valid range is from 0.6 Hz to 19 kHz. The frequency resolution is logarithmic.

There is only one PWM frequency for all channels.

**Parameters** **rate** (*float*) – The frequency to output all digital output PWM signals.

**updateDutyCycle** (*dutyCycle*)

Change the duty-cycle that is being generated on the line.

The resolution of the duty cycle is 8-bit for low frequencies (1kHz or less) but is reduced the higher the frequency of the PWM signal is.

**Parameters** **dutyCycle** (*float*) – The duty-cycle to change to. [0..1]

### 1.4.23 DigitalSource

**class** `wpiplib.DigitalSource` (*channel*, *input*)

Bases: `wpiplib.InterruptableSensorBase`

DigitalSource Interface. The DigitalSource represents all the possible inputs for a counter or a quadrature encoder. The source may be either a digital input or an analog input. If the caller just provides a channel, then a digital input will be constructed and freed when finished for the source. The source can either be a digital input or analog trigger but not both.

**Parameters**

- **channel** (*int*) – Port for the digital input
- **input** (*int*) – True if input, False otherwise



**channels** = <wpilib.resource.Resource object>

**free** ()

**getAnalogTriggerForRouting** ()  
Is this an analog trigger

**Returns** True if this is an analog trigger

**getChannelForRouting** ()  
Get the channel routing number

**Returns** channel routing number

**getModuleForRouting** ()  
Get the module routing number

**Returns** 0

**port**

### 1.4.24 DoubleSolenoid

**class** wpilib.**DoubleSolenoid** (\*args, \*\*kwargs)

Bases: *wpilib.SolenoidBase*

Controls 2 channels of high voltage Digital Output.

The DoubleSolenoid class is typically used for pneumatics solenoids that have two positions controlled by two separate channels.

Constructor.

Arguments can be supplied as positional or keyword. Acceptable positional argument combinations are:

- forwardChannel, reverseChannel
- moduleNumber, forwardChannel, reverseChannel

Alternatively, the above names can be used as keyword arguments.

#### Parameters

- **moduleNumber** – The module number of the solenoid module to use.
- **forwardChannel** – The forward channel number on the PCM (0..7)
- **reverseChannel** – The reverse channel number on the PCM (0..7)

**class** **Value**

Bases: object

Possible values for a DoubleSolenoid.

**kForward** = 1

**kOff** = 0

**kReverse** = 2

DoubleSolenoid.**free** ()

Mark the solenoid as freed.

DoubleSolenoid.**get** ()

Read the current value of the solenoid.

**Returns** The current value of the solenoid.

**Return type** *DoubleSolenoid.Value*

`DoubleSolenoid.isFwdSolenoidBlackListed()`

**Check if the forward solenoid is blacklisted.** If a solenoid is shorted, it is added to the blacklist and disabled until power cycle, or until faults are cleared. See `clearAllPCMStickyFaults()`

**Returns** If solenoid is disabled due to short.

`DoubleSolenoid.isRevSolenoidBlackListed()`

**Check if the reverse solenoid is blacklisted.** If a solenoid is shorted, it is added to the blacklist and disabled until power cycle, or until faults are cleared. See `clearAllPCMStickyFaults()`

**Returns** If solenoid is disabled due to short.

`DoubleSolenoid.set(value)`

Set the value of a solenoid.

**Parameters** `value` (*DoubleSolenoid.Value*) – The value to set (Off, Forward, Reverse)

## 1.4.25 DriverStation

`class wpilib.DriverStation`

Bases: `object`

Provide access to the network communication data to / from the Driver Station.

DriverStation constructor.

The single DriverStation instance is created statically with the instance static member variable, you should never create a DriverStation instance.

`class Alliance`

Bases: `object`

The robot alliance that the robot is a part of

**Blue = 1**

**Invalid = 2**

**Red = 0**

`DriverStation.InAutonomous(entering)`

Only to be used to tell the Driver Station what code you claim to be executing for diagnostic purposes only.

**Parameters** `entering` – If True, starting autonomous code; if False, leaving autonomous code

`DriverStation.InDisabled(entering)`

Only to be used to tell the Driver Station what code you claim to be executing for diagnostic purposes only.

**Parameters** `entering` – If True, starting disabled code; if False, leaving disabled code

`DriverStation.InOperatorControl(entering)`

Only to be used to tell the Driver Station what code you claim to be executing for diagnostic purposes only.

**Parameters** `entering` – If True, starting teleop code; if False, leaving teleop code

`DriverStation.InTest(entering)`

Only to be used to tell the Driver Station what code you claim to be executing for diagnostic purposes only.

**Parameters** `entering` – If True, starting test code; if False, leaving test code

`DriverStation.getAlliance()`

Get the current alliance from the FMS.

**Returns** The current alliance

**Return type** `DriverStation.Alliance`

`DriverStation.getBatteryVoltage()`

Read the battery voltage.

**Returns** The battery voltage in Volts.

`DriverStation.getData()`

Copy data from the DS task for the user. If no new data exists, it will just be returned, otherwise the data will be copied from the DS polling loop.

**static** `DriverStation.getInstance()`

Gets the global instance of the DriverStation

**Returns** `DriverStation`

`DriverStation.getJoystickIsXbox(stick)`

Gets the value of isXbox on a joystick

**Parameters** `stick` – The joystick port number

:returns A boolean that returns the value of isXbox

`DriverStation.getJoystickName(stick)`

Gets the name of a joystick

**Parameters** `stick` – The joystick port number

:returns The joystick name.

`DriverStation.getJoystickType(stick)`

Gets the value of type on a joystick

**Parameters** `stick` – The joystick port number

:returns An integer that returns the value of type.

`DriverStation.getLocation()`

Gets the location of the team's driver station controls.

**Returns** The location of the team's driver station controls: 1, 2, or 3

`DriverStation.getMatchTime()`

Return the approximate match time. The FMS does not currently send the official match time to the robots, but does send an approximate match time. The value will count down the time remaining in the current period (auto or teleop).

**Warning:** This is not an official time (so it cannot be used to argue with referees or guarantee that a function will trigger before a match ends).

The Practice Match function of the DS approximates the behaviour seen on the field.

**Returns** Time remaining in current match period (auto or teleop) in seconds

`DriverStation.getStickAxis(stick, axis)`

Get the value of the axis on a joystick. This depends on the mapping of the joystick connected to the specified port.

**Parameters**

- **stick** – The joystick port number
- **axis** – The analog axis value to read from the joystick.

**Returns** The value of the axis on the joystick.

`DriverStation.getStickAxisCount (stick)`

Returns the number of axes on a given joystick port

**Parameters** **stick** – The joystick port number

**Returns** The number of axes on the indicated joystick

`DriverStation.getStickButton (stick, button)`

The state of a button on the joystick.

**Parameters**

- **stick** – The joystick port number
- **button** – The button number to be read.

**Returns** The state of the button.

`DriverStation.getStickButtonCount (stick)`

Gets the number of buttons on a joystick

**Parameters** **stick** – The joystick port number

**Returns** The number of buttons on the indicated joystick.

`DriverStation.getStickButtons (stick)`

The state of all the buttons on the joystick.

**Parameters** **stick** – The joystick port number

**Returns** The state of all buttons, as a bit array.

`DriverStation.getStickPOV (stick, pov)`

Get the state of a POV on the joystick.

**Parameters**

- **stick** – The joystick port number
- **pov** – which POV

**Returns** The angle of the POV in degrees, or -1 if the POV is not pressed.

`DriverStation.getStickPOVCount (stick)`

Returns the number of POVs on a given joystick port

**Parameters** **stick** – The joystick port number

**Returns** The number of POVs on the indicated joystick

`DriverStation.isAutonomous ()`

Gets a value indicating whether the Driver Station requires the robot to be running in autonomous mode.

**Returns** True if autonomous mode should be enabled, False otherwise.

`DriverStation.isBrownedOut ()`

Check if the system is browned out.

**Returns** True if the system is browned out.

`DriverStation.isDSAttached ()`

Is the driver station attached to the robot?

**Returns** True if the robot is being controlled by a driver station.

`DriverStation.isDisabled()`

Gets a value indicating whether the Driver Station requires the robot to be disabled.

**Returns** True if the robot should be disabled, False otherwise.

`DriverStation.isEnabled()`

Gets a value indicating whether the Driver Station requires the robot to be enabled.

**Returns** True if the robot is enabled, False otherwise.

`DriverStation.isFMSAttached()`

Is the driver station attached to a Field Management System?

**Returns** True if the robot is competing on a field being controlled by a Field Management System

`DriverStation.isNewControlData()`

Has a new control packet from the driver station arrived since the last time this function was called?

**Returns** True if the control data has been updated since the last call.

`DriverStation.isOperatorControl()`

Gets a value indicating whether the Driver Station requires the robot to be running in operator-controlled mode.

**Returns** True if operator-controlled mode should be enabled, False otherwise.

`DriverStation.isSysActive()`

Gets a value indicating whether the FPGA outputs are enabled. The outputs may be disabled if the robot is disabled or e-stopped, the watchdog has expired, or if the roboRIO browns out.

**Returns** True if the FPGA outputs are enabled.

`DriverStation.isTest()`

Gets a value indicating whether the Driver Station requires the robot to be running in test mode.

**Returns** True if test mode should be enabled, False otherwise.

`DriverStation.kJoystickPorts = 6`

The number of joystick ports

`DriverStation.release()`

Kill the thread

**static** `DriverStation.reportError(error, printTrace)`

Report error to Driver Station, and also prints error to `sys.stderr`. Optionally appends stack trace to error message.

**Parameters** `printTrace` – If True, append stack trace to error string

`DriverStation.task()`

Provides the service routine for the DS polling thread.

`DriverStation.waitForData(timeout=None)`

Wait for new data or for timeout, whichever comes first. If timeout is None, wait for new data only.

**Parameters** `timeout` – The maximum time in milliseconds to wait.

## 1.4.26 Encoder

**class** `wpilib.Encoder(*args, **kwargs)`

Bases: `wpilib.SensorBase`

Reads from quadrature encoders.

Quadrature encoders are devices that count shaft rotation and can sense direction. The output of the `QuadEncoder` class is an integer that can count either up or down, and can go negative for reverse direction counting. When creating `QuadEncoders`, a direction is supplied that changes the sense of the output to make code more readable if the encoder is mounted such that forward movement generates negative values. Quadrature encoders have two digital outputs, an A Channel and a B Channel that are out of phase with each other to allow the FPGA to do direction sensing.

All encoders will immediately start counting - `reset()` them if you need them to be zeroed before use.

Instance variables:

- `aSource`: The A phase of the quad encoder
- `bSource`: The B phase of the quad encoder
- `indexSource`: The index source (available on some encoders)

Encoder constructor. Construct a `Encoder` given a and b channels and optionally an index channel.

The encoder will start counting immediately.

The a, b, and optional index channel arguments may be either channel numbers or *DigitalSource* sources. There may also be a boolean `reverseDirection`, and an `encodingType` according to the following list.

- `aSource`, `bSource`
- `aSource`, `bSource`, `reverseDirection`
- `aSource`, `bSource`, `reverseDirection`, `encodingType`
- `aSource`, `bSource`, `indexSource`, `reverseDirection`
- `aSource`, `bSource`, `indexSource`
- `aChannel`, `bChannel`
- `aChannel`, `bChannel`, `reverseDirection`
- `aChannel`, `bChannel`, `reverseDirection`, `encodingType`
- `aChannel`, `bChannel`, `indexChannel`, `reverseDirection`
- `aChannel`, `bChannel`, `indexChannel`

For positional arguments, if the passed object has a `getChannelForRouting` function, it is assumed to be a `DigitalSource`.

Alternatively, sources and/or channels may be passed as keyword arguments. The behavior of specifying both a source and a number for the same channel is undefined, as is passing both a positional and a keyword argument for the same channel.

In addition, keyword parameters may be provided for `reverseDirection` and `inputType`.

### Parameters

- **`aSource`** – The source that should be used for the a channel.
- **`bSource`** – The source that should be used for the b channel.
- **`indexSource`** – The source that should be used for the index channel.
- **`aChannel1`** – The digital input index that should be used for the a channel.
- **`bChannel1`** – The digital input index that should be used for the b channel.
- **`indexChannel1`** – The digital input index that should be used for the index channel.

- **reverseDirection** – Represents the orientation of the encoder and inverts the output values if necessary so forward represents positive values. Defaults to False if unspecified.
- **encodingType** (*Encoder.EncodingType*) – Either k1X, k2X, or k4X to indicate 1X, 2X or 4X decoding. If 4X is selected, then an encoder FPGA object is used and the returned counts will be 4x the encoder spec'd value since all rising and falling edges are counted. If 1X or 2X are selected then a counter object will be used and the returned value will either exactly match the spec'd count or be double (2x) the spec'd count. Defaults to k4X if unspecified.

**class** `Encoder.EncodingType`Bases: `object`

The number of edges for the counterbase to increment or decrement on

**k1X = 0****k2X = 1****k4X = 2****class** `Encoder.IndexingType`Bases: `object`**kResetOnFallingEdge = 2****kResetOnRisingEdge = 3****kResetWhileHigh = 0****kResetWhileLow = 1****class** `Encoder.PIDSourceType`Bases: `object`A description for the type of output value to provide to a *PIDController***kDisplacement = 0****kRate = 1**`Encoder.decodingScaleFactor()`

The scale needed to convert a raw counter value into a number of encoder pulses.

`Encoder.encoder``Encoder.free()``Encoder.get()`

Gets the current count. Returns the current count on the Encoder. This method compensates for the decoding type.

**Returns** Current count from the Encoder adjusted for the 1x, 2x, or 4x scale factor.`Encoder.getDirection()`

The last direction the encoder value changed.

**Returns** The last direction the encoder value changed.`Encoder.getDistance()`

Get the distance the robot has driven since the last reset.

**Returns** The distance driven since the last reset as scaled by the value from *setDistancePerPulse()*.`Encoder.getEncodingScale()`

**Returns** The encoding scale factor 1x, 2x, or 4x, per the requested encodingType. Used to divide raw edge counts down to spec'd counts.

Encoder.**getFPGAIndex**()

**Returns** The Encoder's FPGA index

Encoder.**getPIDSourceType**()

Encoder.**getPeriod**()

Returns the period of the most recent pulse. Returns the period of the most recent Encoder pulse in seconds. This method compensates for the decoding type.

Deprecated since version Use: *getRate()* in favor of this method. This returns unscaled periods and *getRate()* scales using value from *getDistancePerPulse()*.

**Returns** Period in seconds of the most recent pulse.

Encoder.**getRate**()

Get the current rate of the encoder. Units are distance per second as scaled by the value from *setDistancePerPulse()*.

**returns** The current rate of the encoder.

Encoder.**getRaw**()

Gets the raw value from the encoder. The raw value is the actual count unscaled by the 1x, 2x, or 4x scale factor.

**Returns** Current raw count from the encoder

Encoder.**getSamplesToAverage**()

Get the Samples to Average which specifies the number of samples of the timer to average when calculating the period. Perform averaging to account for mechanical imperfections or as oversampling to increase resolution.

**Returns** The number of samples being averaged (from 1 to 127)

Encoder.**getStopped**()

Determine if the encoder is stopped. Using the MaxPeriod value, a boolean is returned that is True if the encoder is considered stopped and False if it is still moving. A stopped encoder is one where the most recent pulse width exceeds the MaxPeriod.

**Returns** True if the encoder is considered stopped.

Encoder.**pidGet**()

Implement the PIDSource interface.

**Returns** The current value of the selected source parameter.

Encoder.**reset**()

Reset the Encoder distance to zero. Resets the current count to zero on the encoder.

Encoder.**setDistancePerPulse**(*distancePerPulse*)

Set the distance per pulse for this encoder. This sets the multiplier used to determine the distance driven based on the count value from the encoder. Do not include the decoding type in this scale. The library already compensates for the decoding type. Set this value based on the encoder's rated Pulses per Revolution and factor in gearing reductions following the encoder shaft. This distance can be in any units you like, linear or angular.

**Parameters distancePerPulse** – The scale factor that will be used to convert pulses to useful units.

Encoder.**setIndexSource**(*source, indexing\_type=3*)

Set the index source for the encoder. When this source rises, the encoder count automatically resets.



**Parameters**

- **source** – Either an initialized DigitalSource or a DIO channel number
- **indexing\_type** – The state that will cause the encoder to reset

**Type** Either a DigitalInput or number

**Type** A value from `wpiplib.IndexingType`

`Encoder.setMaxPeriod` (*maxPeriod*)

Sets the maximum period for stopped detection. Sets the value that represents the maximum period of the Encoder before it will assume that the attached device is stopped. This timeout allows users to determine if the wheels or other shaft has stopped rotating. This method compensates for the decoding type.

**Parameters** **maxPeriod** – The maximum time between rising and falling edges before the FPGA will report the device stopped. This is expressed in seconds.

`Encoder.setMinRate` (*minRate*)

Set the minimum rate of the device before the hardware reports it stopped.

**Parameters** **minRate** – The minimum rate. The units are in distance per second as scaled by the value from `setDistancePerPulse()`.

`Encoder.setPIDSourceType` (*pidSource*)

Set which parameter of the encoder you are using as a process control variable. The encoder class supports the rate and distance parameters.

**Parameters** **pidSource** – An enum to select the parameter.

`Encoder.setReverseDirection` (*reverseDirection*)

Set the direction sensing for this encoder. This sets the direction sensing on the encoder so that it could count in the correct software direction regardless of the mounting.

**Parameters** **reverseDirection** – True if the encoder direction should be reversed

`Encoder.setSamplesToAverage` (*samplesToAverage*)

Set the Samples to Average which specifies the number of samples of the timer to average when calculating the period. Perform averaging to account for mechanical imperfections or as oversampling to increase resolution.

TODO: Should this raise an exception, so that the user has to deal with giving an incorrect value?

**Parameters** **samplesToAverage** – The number of samples to average from 1 to 127.

## 1.4.27 Filter

`class wpiplib.Filter` (*source*)

Bases: object

Superclass for filters

Constructor.

**Parameters** **source** (*PIDSource*, callable) –

**get** ()

Returns the current filter estimate without also inserting new data as `pidGet()` would do.

**Returns** The current filter estimate

**getPIDSourceType** ()

**pidGet** ()

**pidGetSource ()**  
Calls PIDGet() of source

**Returns** Current value of source

**reset ()**  
Reset the filter state

**setPIDSourceType (pidSourceType)**

## 1.4.28 GearTooth

**class** `wpiplib.GearTooth (channel, directionSensitive=False)`  
Bases: `wpiplib.Counter`

Interface to the gear tooth sensor supplied by FIRST

Currently there is no reverse sensing on the gear tooth sensor, but in future versions we might implement the necessary timing in the FPGA to sense direction.

Construct a GearTooth sensor.

### Parameters

- **channel** (*int*) – The DIO channel index or DigitalSource that the sensor is connected to.
- **directionSensitive** (*bool*) – True to enable the pulse length decoding in hardware to specify count direction. Defaults to False.

**enableDirectionSensing (directionSensitive)**

**free ()**

**kGearToothThreshold = 5.5e-05**

## 1.4.29 GyroBase

**class** `wpiplib.GyroBase`  
Bases: `wpiplib.SensorBase`

GyroBase is the common base class for Gyro implementations such as `AnalogGyro`.

**class** `PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement = 0**

**kRate = 1**

`GyroBase.calibrate ()`

`GyroBase.getAngle ()`

`GyroBase.getPIDSourceType ()`

`GyroBase.getRate ()`

`GyroBase.pidGet ()`

Get the output of the gyro for use with PIDControllers. May be the angle or rate depending on the set `PIDSourceType`

**Returns** the current angle according to the gyro

**Return type** float

GyroBase.**reset** ()

GyroBase.**setPIDSourceType** (*pidSource*)

Set which parameter of the gyro you are using as a process control variable. The Gyro class supports the rate and angle parameters.

**Parameters** **pidSource** (*PIDSource.PIDSourceType*) – An enum to select the parameter.

### 1.4.30 I2C

**class** wpilib.**I2C** (*port, deviceAddress, simPort=None*)

Bases: object

I2C bus interface class.

This class is intended to be used by sensor (and other I2C device) drivers. It probably should not be used directly.

Example usage:

```
i2c = wpilib.I2C(wpilib.I2C.Port.kOnboard, 4)

# Write bytes 'text', and receive 4 bytes in data
data = i2c.transaction(b'text', 4)
```

Constructor.

#### Parameters

- **port** (*I2C.Port*) – The I2C port the device is connected to.
- **deviceAddress** – The address of the device on the I2C bus.
- **simPort** – This must be an object that implements all of the i2c\* functions from hal\_impl that you use. See `test_i2c.py` for an example.

**class** **Port**

Bases: object

**kMXP = 1**

**kOnboard = 0**

I2C.**addressOnly** ()

Attempt to address a device on the I2C bus.

This allows you to figure out if there is a device on the I2C bus that responds to the address specified in the constructor.

**Returns** Transfer Aborted... False for success, True for aborted.

I2C.**broadcast** (*registerAddress, data*)

Send a broadcast write to all devices on the I2C bus.

**Warning:** This is not currently implemented!

#### Parameters

- **registerAddress** – The register to write on all devices on the bus.
- **data** – The value to write to the devices.

`I2C.free()`

`I2C.port`

`I2C.read(registerAddress, count)`

Execute a read transaction with the device.

Read bytes from a device. Most I2C devices will auto-increment the register pointer internally allowing you to read consecutive registers on a device in a single transaction.

**Parameters**

- **registerAddress** – The register to read first in the transaction.
- **count** – The number of bytes to read in the transaction.

**Returns** The data read from the device.

**Return type** iterable of bytes

`I2C.readOnly(count)`

Execute a read only transaction with the device.

Read bytes from a device. This method does not write any data to prompt the device.

**Parameters** **count** – The number of bytes to read in the transaction.

**Returns** The data read from the device.

**Return type** iterable of bytes

`I2C.transaction(dataToSend, receiveSize)`

Generic transaction.

This is a lower-level interface to the I2C hardware giving you more control over each transaction.

**Parameters**

- **dataToSend** (*iterable of bytes*) – Data to send as part of the transaction.
- **receiveSize** (*int*) – Number of bytes to read from the device. [0..7]

**Returns** Data received from the device.

**Return type** iterable of bytes

`I2C.verifySensor(registerAddress, expected)`

Verify that a device's registers contain expected values.

Most devices will have a set of registers that contain a known value that can be used to identify them. This allows an I2C device driver to easily verify that the device contains the expected value.

The device must support and be configured to use register auto-increment.

**Parameters**

- **registerAddress** – The base register to start reading from the device.
- **expected** – The values expected from the device.

**Returns** True if the sensor was verified to be connected

`I2C.write(registerAddress, data)`

Execute a write transaction with the device.

Write a single byte to a register on a device and wait until the transaction is complete.

**Parameters**

- **registerAddress** – The address of the register on the device to be written.
- **data** – The byte to write to the register on the device.

**Returns** Transfer Aborted... False for success, True for aborted.

I2C.**writeBulk** (*data*)

Execute a write transaction with the device.

Write multiple bytes to a register on a device and wait until the transaction is complete.

**Parameters** **data** (*iterable of bytes*) – The data to write to the device.

**Returns** Transfer Aborted... False for success, True for aborted.

Usage:

```
# send byte string
failed = spi.writeBulk(b'stuff')

# send list of integers
failed = spi.write([0x01, 0x02])
```

### 1.4.31 InterruptableSensorBase

**class** `wpiplib.InterruptableSensorBase`

Bases: `wpiplib.SensorBase`

Base for sensors to be used with interrupts

Create a new InterruptableSensorBase

**allocateInterrupts** (*watcher*)

Allocate the interrupt

**Parameters** **watcher** – True if the interrupt should be in synchronous mode where the user program will have to explicitly wait for the interrupt to occur.

**cancelInterrupts** ()

Cancel interrupts on this device. This deallocates all the chipobject structures and disables any interrupts.

**disableInterrupts** ()

Disable Interrupts without without deallocating structures.

**enableInterrupts** ()

Enable interrupts to occur on this input. Interrupts are disabled when the RequestInterrupt call is made. This gives time to do the setup of the other options before starting to field interrupts.

**getAnalogTriggerForRouting** ()

**getChannelForRouting** ()

**getModuleForRouting** ()

**interrupt**

**interrupts** = `<wpiplib.resource.Resource object>`

**readFallingTimestamp** ()

Return the timestamp for the falling interrupt that occurred most recently. This is in the same time domain as `getClock()`. The falling-edge interrupt should be enabled with `setUpSourceEdge`.

**Returns** Timestamp in seconds since boot.

**readRisingTimestamp ()**

Return the timestamp for the rising interrupt that occurred most recently. This is in the same time domain as `getClock()`. The rising-edge interrupt should be enabled with `setUpSourceEdge`.

**Returns** Timestamp in seconds since boot.

**requestInterrupts (handler=None)**

Request one of the 8 interrupts asynchronously on this digital input.

**Parameters** **handler** – (optional) The function that will be called whenever there is an interrupt on this device. Request interrupts in synchronous mode where the user program interrupt handler will be called when an interrupt occurs. The default is interrupt on rising edges only. If not specified, the user program will have to explicitly wait for the interrupt to occur using `waitForInterrupt`.

**setUpSourceEdge (risingEdge, fallingEdge)**

Set which edge to trigger interrupts on

**Parameters**

- **risingEdge** – True to interrupt on rising edge
- **fallingEdge** – True to interrupt on falling edge

**waitForInterrupt (timeout, ignorePrevious=True)**

In synchronous mode, wait for the defined interrupt to occur. You should **NOT** attempt to read the sensor from another thread while waiting for an interrupt. This is not threadsafe, and can cause memory corruption

**Parameters**

- **timeout** – Timeout in seconds
- **ignorePrevious** – If True (default), ignore interrupts that happened before `waitForInterrupt` was called.

## 1.4.32 IterativeRobot

**class** `wpiLib.IterativeRobot`

Bases: `wpiLib.RobotBase`

`IterativeRobot` implements a specific type of Robot Program framework, extending the `RobotBase` class.

The `IterativeRobot` class is intended to be subclassed by a user creating a robot program.

This class is intended to implement the “old style” default code, by providing the following functions which are called by the main loop, `startCompetition()`, at the appropriate times:

- `robotInit()` – provide for initialization at robot power-on

`init()` functions – each of the following functions is called once when the appropriate mode is entered:

- `disabledInit()` – called only when first disabled
- `autonomousInit()` – called each and every time autonomous is entered from another mode
- `teleopInit()` – called each and every time teleop is entered from another mode
- `testInit()` – called each and every time test mode is entered from another mode

`Periodic()` functions – each of these functions is called iteratively at the appropriate periodic rate (aka the “slow loop”). The period of the iterative robot is synced to the driver station control packets, giving a periodic frequency of about 50Hz (50 times per second).

- `disabledPeriodic()`

- `autonomousPeriodic()`
- `teleopPeriodic()`
- `testPeriodic()`

Constructor for `RobotIterativeBase`.

The constructor initializes the instance variables for the robot to indicate the status of initialization for disabled, autonomous, and teleop code.

**Warning:** If you override `__init__` in your robot class, you must call the base class constructor. This must be used to ensure that the communications code starts.

#### **autonomousInit()**

Initialization code for autonomous mode should go here.

Users should override this method for initialization code which will be called each time the robot enters autonomous mode.

#### **autonomousPeriodic()**

Periodic code for autonomous mode should go here.

Users should override this method for code which will be called periodically at a regular rate while the robot is in autonomous mode.

#### **disabledInit()**

Initialization code for disabled mode should go here.

Users should override this method for initialization code which will be called each time the robot enters disabled mode.

#### **disabledPeriodic()**

Periodic code for disabled mode should go here.

Users should override this method for code which will be called periodically at a regular rate while the robot is in disabled mode.

#### **logger = <logging.Logger object>**

A python logging object that you can use to send messages to the log. It is recommended to use this instead of print statements.

#### **nextPeriodReady()**

Determine if the appropriate next periodic function should be called. Call the periodic functions whenever a packet is received from the Driver Station, or about every 20ms.

**Return type** bool

#### **robotInit()**

Robot-wide initialization code should go here.

Users should override this method for default Robot-wide initialization which will be called when the robot is first powered on. It will be called exactly 1 time.

---

**Note:** It is simpler to override this function instead of defining a constructor for your robot class

---

#### **startCompetition()**

Provide an alternate “main loop” via `startCompetition()`.

#### **teleopInit()**

Initialization code for teleop mode should go here.

Users should override this method for initialization code which will be called each time the robot enters teleop mode.

**teleopPeriodic ()**

Periodic code for teleop mode should go here.

Users should override this method for code which will be called periodically at a regular rate while the robot is in teleop mode.

**testInit ()**

Initialization code for test mode should go here.

Users should override this method for initialization code which will be called each time the robot enters test mode.

**testPeriodic ()**

Periodic code for test mode should go here.

Users should override this method for code which will be called periodically at a regular rate while the robot is in test mode.

### 1.4.33 Jaguar

**class** `wpiplib.Jaguar` (*channel*)

Bases: `wpiplib.SafePWM`

Texas Instruments / Vex Robotics Jaguar Speed Controller as a PWM device.

**See also:**

`CANJaguar` for CAN control of a Jaguar

Constructor.

**Parameters** `channel` – The PWM channel that the Jaguar is attached to. 0-9 are on-board, 10-19 are on the MXP port

**free ()**

**get ()**

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted ()**

Common interface for inverting the direction of a speed controller.

**Returns** The state of inversion (True is inverted)

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the `PIDController`.

**set** (*speed*, *syncGroup=0*)

Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.



- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting the direction of a speed controller.

**Parameters** **isInverted** – The state of inversion (True is inverted).

### 1.4.34 Joystick

**class** `wpiplib.Joystick` (*port, numAxisTypes=None, numButtonTypes=None*)

Bases: `object`

Handle input from standard Joysticks connected to the Driver Station.

This class handles standard input that comes from the Driver Station. Each time a value is requested the most recent value is returned. There is a single class instance for each joystick and the mapping of ports to hardware buttons depends on the code in the driver station.

Construct an instance of a joystick.

The joystick index is the usb port on the drivers station.

This constructor is intended for use by subclasses to configure the number of constants for axes and buttons.

#### Parameters

- **port** (*int*) – The port on the driver station that the joystick is plugged into.
- **numAxisTypes** (*int*) – The number of axis types.
- **numButtonTypes** (*int*) – The number of button types.

**class** `AxisType`

Bases: `object`

Represents an analog axis on a joystick.

**kNumAxis** = 5

**kThrottle** = 4

**kTwist** = 3

**kX** = 0

**kY** = 1

**kZ** = 2

**class** `Joystick.ButtonType`

Bases: `object`

Represents a digital button on the Joystick

**kNumButton** = 2

**kTop** = 1

**kTrigger** = 0

**class** `Joystick.RumbleType`

Bases: `object`

Represents a rumble output on the Joystick

**kLeftRumble\_val** = 0

`kRightRumble_val = 1`

`Joystick.flush_outputs()`

Flush all joystick HID & rumble output values to the HAL

`Joystick.getAxis(axis)`

For the current joystick, return the axis determined by the argument.

This is for cases where the joystick axis is returned programmatically, otherwise one of the previous functions would be preferable (for example `getX()`).

**Parameters** `axis` (`Joystick.AxisType`) – The axis to read.

**Returns** The value of the axis.

**Return type** float

`Joystick.getAxisChannel(axis)`

Get the channel currently associated with the specified axis.

**Parameters** `axis` (`int`) – The axis to look up the channel for.

**Returns** The channel for the axis.

**Return type** int

`Joystick.getAxisCount()`

For the current joystick, return the number of axis

`Joystick.getBumper(hand=None)`

This is not supported for the Joystick.

This method is only here to complete the GenericHID interface.

**Parameters** `hand` – This parameter is ignored for the Joystick class and is only here to complete the GenericHID interface.

**Returns** The state of the bumper (always False)

**Return type** bool

`Joystick.getButton(button)`

Get buttons based on an enumerated type.

The button type will be looked up in the list of buttons and then read.

**Parameters** `button` (`Joystick.ButtonType`) – The type of button to read.

**Returns** The state of the button.

**Return type** bool

`Joystick.getButtonCount()`

For the current joystick, return the number of buttons

:rtype int

`Joystick.getDirectionDegrees()`

Get the direction of the vector formed by the joystick and its origin in degrees.

**Returns** The direction of the vector in degrees

**Return type** float

`Joystick.getDirectionRadians()`

Get the direction of the vector formed by the joystick and its origin in radians.

**Returns** The direction of the vector in radians

**Return type** float

`Joystick.getIsXbox()`

Get the value of isXbox for the current joystick.

**Returns** A boolean that is true if the controller is an xbox controller.

`Joystick.getMagnitude()`

Get the magnitude of the direction vector formed by the joystick's current position relative to its origin.

**Returns** The magnitude of the direction vector

**Return type** float

`Joystick.getName()`

Get the name of the current joystick.

**Returns** The name of the current joystick.

`Joystick.getPOV(pov=0)`

Get the state of a POV on the joystick.

**Parameters** `pov` (*int*) – which POV (default is 0)

**Returns** The angle of the POV in degrees, or -1 if the POV is not pressed.

**Return type** float

`Joystick.getPOVCount()`

For the current joystick, return the number of POVs

**Return type** int

`Joystick.getRawAxis(axis)`

Get the value of the axis.

**Parameters** `axis` (*int*) – The axis to read, starting at 0.

**Returns** The value of the axis.

**Return type** float

`Joystick.getRawButton(button)`

Get the button value (starting at button 1).

The buttons are returned in a single 16 bit value with one bit representing the state of each button. The appropriate button is returned as a boolean value.

**Parameters** `button` (*int*) – The button number to be read (starting at 1).

**Returns** The state of the button.

**Return type** bool

`Joystick.getThrottle()`

Get the throttle value of the current joystick.

This depends on the mapping of the joystick connected to the current port.

**Returns** The Throttle value of the joystick.

**Return type** float

`Joystick.getTop(hand=None)`

Read the state of the top button on the joystick.

Look up which button has been assigned to the top and read its state.

**Parameters** **hand** – This parameter is ignored for the Joystick class and is only here to complete the GenericHID interface.

**Returns** The state of the top button.

**Return type** bool

`Joystick.getTrigger(hand=None)`

Read the state of the trigger on the joystick.

Look up which button has been assigned to the trigger and read its state.

**Parameters** **hand** – This parameter is ignored for the Joystick class and is only here to complete the GenericHID interface.

**Returns** The state of the trigger.

**Return type** bool

`Joystick.getTwist()`

Get the twist value of the current joystick.

This depends on the mapping of the joystick connected to the current port.

**Returns** The Twist value of the joystick.

**Return type** float

`Joystick.getType()`

Get the HID type of the current joystick.

**Returns** The HID type value of the current joystick.

`Joystick.getX(hand=None)`

Get the X value of the joystick.

This depends on the mapping of the joystick connected to the current port.

**Parameters** **hand** – Unused

**Returns** The X value of the joystick.

**Return type** float

`Joystick.getY(hand=None)`

Get the Y value of the joystick.

This depends on the mapping of the joystick connected to the current port.

**Parameters** **hand** – Unused

**Returns** The Y value of the joystick.

**Return type** float

`Joystick.getZ(hand=None)`

Get the Z value of the joystick.

This depends on the mapping of the joystick connected to the current port.

**Parameters** **hand** – Unused

**Returns** The Z value of the joystick.

**Return type** float

`Joystick.kDefaultThrottleAxis = 3`

`Joystick.kDefaultTopButton = 2`

```
Joystick.kDefaultTriggerButton = 1
```

```
Joystick.kDefaultTwistAxis = 2
```

```
Joystick.kDefaultXAxis = 0
```

```
Joystick.kDefaultYAxis = 1
```

```
Joystick.kDefaultZAxis = 2
```

```
Joystick.setAxisChannel (axis, channel)
```

Set the channel associated with a specified axis.

#### Parameters

- **axis** (*int*) – The axis to set the channel for.
- **channel** (*int*) – The channel to set the axis to.

```
Joystick.setOutput (outputNumber, value)
```

Set a single HID output value for the joystick.

#### Parameters

- **outputNumber** – The index of the output to set (1-32)
- **value** – The value to set the output to.

```
Joystick.setOutputs (value)
```

Set all HID output values for the joystick.

**Parameters value** (*int*) – The 32 bit output value (1 bit for each output)

```
Joystick.setRumble (type, value)
```

Set the rumble output for the joystick. The DS currently supports 2 rumble values, left rumble and right rumble

#### Parameters

- **type** (*Joystick.RumbleType*) – Which rumble value to set
- **value** (*float*) – The normalized value (0 to 1) to set the rumble to

## 1.4.35 LinearDigitalFilter

```
class wpilib.LinearDigitalFilter (source, ffGains, fbGains)
```

Bases: *wpilib.Filter*

This class implements a linear, digital filter. All types of FIR and IIR filters are supported. Static factory methods are provided to create commonly used types of filters.

Filters are of the form:

$$y[n] = (b_0 * x[n] + b_1 * x[n-1] + \dots + b_P * x[n-P]) - (a_0 * y[n-1] + a_2 * y[n-2] + \dots + a_Q * y[n-Q])$$

Where:

- $y[n]$  is the output at time “n”
- $x[n]$  is the input at time “n”
- $y[n-1]$  is the output from the LAST time step (“n-1”)
- $x[n-1]$  is the input from the LAST time step (“n-1”)
- $b_0 \dots b_P$  are the “feedforward” (FIR) gains

- $a_0 \dots a_Q$  are the “feedback” (IIR) gains

---

**Note:** IMPORTANT! Note the “-” sign in front of the feedback term! This is a common convention in signal processing.

---

What can linear filters do? Basically, they can filter, or diminish, the effects of undesirable input frequencies. High frequencies, or rapid changes, can be indicative of sensor noise or be otherwise undesirable. A “low pass” filter smoothes out the signal, reducing the impact of these high frequency components. Likewise, a “high pass” filter gets rid of slow-moving signal components, letting you detect large changes more easily.

Example FRC applications of filters:

- Getting rid of noise from an analog sensor input (note: the roboRIO’s FPGA can do this faster in hardware)
- Smoothing out joystick input to prevent the wheels from slipping or the robot from tipping
- Smoothing motor commands so that unnecessary strain isn’t put on electrical or mechanical components
- If you use clever gains, you can make a PID controller out of this class!

For more on filters, I highly recommend the following articles:

- [http://en.wikipedia.org/wiki/Linear\\_filter](http://en.wikipedia.org/wiki/Linear_filter)
- [http://en.wikipedia.org/wiki/Iir\\_filter](http://en.wikipedia.org/wiki/Iir_filter)
- [http://en.wikipedia.org/wiki/Fir\\_filter](http://en.wikipedia.org/wiki/Fir_filter)

---

**Note:** `pidGet()` should be called by the user on a known, regular period. You can set up a Notifier to do this (look at the `PIDController` class), or do it “inline” with code in a periodic function.

---

---

**Note:** For ALL filters, gains are necessarily a function of frequency. If you make a filter that works well for you at, say, 100Hz, you will most definitely need to adjust the gains if you then want to run it at 200Hz! Combining this with Note 1 - the impetus is on YOU as a developer to make sure `pidGet()` gets called at the desired, constant frequency!

---

There are static methods you can use to build common filters:

- `highPass()`
- `movingAverage()`
- `singlePoleIIR()`

Constructor. Create a linear FIR or IIR filter

### Parameters

- **source** (`PIDSource`, callable) – The `PIDSource` object that is used to get values
- **ffGains** (`list`, `tuple`) – The “feed forward” or FIR gains
- **fbGains** (`list`, `tuple`) – The “feed back” or IIR gains

**get()**

Returns the current filter estimate without also inserting new data as `pidGet()` would do.

**Returns** The current filter estimate

**static highPass** (*source, timeConstant, period*)

Creates a first-order high-pass filter of the form:

$$y[n] = \text{gain} * x[n] + (-\text{gain}) * x[n-1] + \text{gain} * y[n-1]$$

where  $\text{gain} = e^{(-dt / T)}$ , T is the time constant in seconds

This filter is stable for time constants greater than zero

#### Parameters

- **source** (*PIDSource*, callable) – The PIDSource object that is used to get values
- **timeConstant** (*float*) – The discrete-time time constant in seconds
- **period** (*float*) – The period in seconds between samples taken by the user

Returns *LinearDigitalFilter*

**static movingAverage** (*source, taps*)

Creates a K-tap FIR moving average filter of the form:

$$y[n] = 1/k * (x[k] + x[k-1] + \dots + x[0])$$

This filter is always stable.

#### Parameters

- **source** (*PIDSource*, callable) – The PIDSource object that is used to get values
- **taps** – The number of samples to average over. Higher = smoother but slower

Raises *ValueError* if number of taps is less than 1

Returns *LinearDigitalFilter*

**pidGet** ()

Calculates the next value of the filter

Returns The filtered value at this step

**reset** ()

Reset the filter state

**static singlePoleIIR** (*source, timeConstant, period*)

Creates a one-pole IIR low-pass filter of the form:

$$y[n] = (1-\text{gain}) * x[n] + \text{gain} * y[n-1]$$

Where  $\text{gain} = e^{(-dt / T)}$ , T is the time constant in seconds

This filter is stable for time constants greater than zero

#### Parameters

- **source** (*PIDSource*, callable) – The PIDSource object that is used to get values
- **timeConstant** (*float*) – The discrete-time time constant in seconds
- **period** (*float*) – The period in seconds between samples taken by the user

Returns *LinearDigitalFilter*

### 1.4.36 LiveWindow

class `wpiLib.LiveWindow`

Bases: `object`

The public interface for putting sensors and actuators on the LiveWindow.

**static addActuator** (*subsystem, name, component*)

Add an Actuator associated with the subsystem and with call it by the given name.

**Parameters**

- **subsystem** – The subsystem this component is part of.
- **name** – The name of this component.
- **component** – A LiveWindowSendable component that represents an actuator.

**static addActuatorChannel** (*moduleType, channel, component*)

Add Actuator to LiveWindow. The components are shown with the module type, slot and channel like this: Servo[0,2] for a servo object connected to the first digital module and PWM port 2.

**Parameters**

- **moduleType** – A string that defines the module name in the label for the value
- **channel** – The channel number the device is plugged into (usually PWM)
- **component** – The reference to the object being added

**static addActuatorModuleChannel** (*moduleType, moduleNumber, channel, component*)

Add Actuator to LiveWindow. The components are shown with the module type, slot and channel like this: Servo[0,2] for a servo object connected to the first digital module and PWM port 2.

**Parameters**

- **moduleType** – A string that defines the module name in the label for the value
- **moduleNumber** – The number of the particular module type
- **channel** – The channel number the device is plugged into (usually PWM)
- **component** – The reference to the object being added

**static addSensor** (*subsystem, name, component*)

Add a Sensor associated with the subsystem and with call it by the given name.

**Parameters**

- **subsystem** – The subsystem this component is part of.
- **name** – The name of this component.
- **component** – A LiveWindowSendable component that represents a sensor.

**static addSensorChannel** (*moduleType, channel, component*)

Add Sensor to LiveWindow. The components are shown with the type and channel like this: Gyro[0] for a gyro object connected to the first analog channel.

**Parameters**

- **moduleType** – A string indicating the type of the module used in the naming (above)
- **channel** – The channel number the device is connected to
- **component** – A reference to the object being added

`components = {}`



**firstTime = True**

**static initializeLiveWindowComponents ()**

Initialize all the LiveWindow elements the first time we enter LiveWindow mode. By holding off creating the NetworkTable entries, it allows them to be redefined before the first time in LiveWindow mode. This allows default sensor and actuator values to be created that are replaced with the custom names from users calling addActuator and addSensor.

**liveWindowEnabled = False**

**livewindowTable = None**

**static removeComponent (component)**

Removes a component from LiveWindow.

**Parameters component** – The reference to the object being removed.

**static run ()**

The run method is called repeatedly to keep the values refreshed on the screen in test mode.

**sensors = set()**

**static setEnabled (enabled)**

Set the enabled state of LiveWindow. If it's being enabled, turn off the scheduler and remove all the commands from the queue and enable all the components registered for LiveWindow. If it's being disabled, stop all the registered components and reenable the scheduler.

TODO: add code to disable PID loops when enabling LiveWindow. The commands should reenable the PID loops themselves when they get rescheduled. This prevents arms from starting to move around, etc. after a period of adjusting them in LiveWindow mode.

**statusTable = None**

**static updateValues ()**

Puts all sensor values on the live window.

### 1.4.37 LiveWindowSendable

**class wpilib.LiveWindowSendable**

Bases: *wpilib.Sendable*

A special type of object that can be displayed on the live window.

### 1.4.38 MotorSafety

**class wpilib.MotorSafety**

Bases: *object*

Provides mechanisms to safely shutdown motors if they aren't updated often enough.

The MotorSafety object is constructed for every object that wants to implement the Motor Safety protocol. The helper object has the code to actually do the timing and call the motors stop() method when the timeout expires. The motor object is expected to call the feed() method whenever the motors value is updated.

The constructor for a MotorSafety object. The helper object is constructed for every object that wants to implement the Motor Safety protocol. The helper object has the code to actually do the timing and call the motors stop() method when the timeout expires. The motor object is expected to call the feed() method whenever the motors value is updated.

**DEFAULT\_SAFETY\_EXPIRATION = 0.1**

**check ()**

Check if this motor has exceeded its timeout. This method is called periodically to determine if this motor has exceeded its timeout value. If it has, the stop method is called, and the motor is shut down until its value is updated again.

**static checkMotors ()**

Check the motors to see if any have timed out. This static method is called periodically to poll all the motors and stop any that have timed out.

**feed ()**

Feed the motor safety object. Resets the timer on this object that is used to do the timeouts.

**getExpiration ()**

Retrieve the timeout value for the corresponding motor safety object.

**Returns** the timeout value in seconds.

**Return type** float

**helpers = <\_weakrefset.WeakSet object>**

**helpers\_lock = <\_thread.lock object>**

**isAlive ()**

Determine if the motor is still operating or has timed out.

**Returns** True if the motor is still operating normally and hasn't timed out.

**Return type** float

**isSafetyEnabled ()**

Return the state of the motor safety enabled flag. Return if the motor safety is currently enabled for this device.

**Returns** True if motor safety is enforced for this device

**Return type** bool

**setExpiration (expirationTime)**

Set the expiration time for the corresponding motor safety object.

**Parameters** **expirationTime** (*float*) – The timeout value in seconds.

**setSafetyEnabled (enabled)**

Enable/disable motor safety for this device. Turn on and off the motor safety option for this PWM object.

**Parameters** **enabled** (*bool*) – True if motor safety is enforced for this object

### 1.4.39 PIDController

**class** `wplib.PIDController (*args, **kwargs)`

Bases: `wplib.LiveWindowSendable`

Can be used to control devices via a PID Control Loop.

Creates a separate thread which reads the given *PIDSource* and takes care of the integral calculations, as well as writing the given *PIDOutput*.

Allocate a PID object with the given constants for P, I, D, and F

Arguments can be structured as follows:

- Kp, Ki, Kd, Kf, PIDSource, PIDOutput, period
- Kp, Ki, Kd, PIDSource, PIDOutput, period

- Kp, Ki, Kd, PIDSource, PIDOutput
- Kp, Ki, Kd, Kf, PIDSource, PIDOutput

### Parameters

- **Kp** (*float or int*) – the proportional coefficient
- **Ki** (*float or int*) – the integral coefficient
- **Kd** (*float or int*) – the derivative coefficient
- **Kf** (*float or int*) – the feed forward term
- **source** (A function, or an object that implements *PIDSource*) – Called to get values
- **output** (A function, or an object that implements *PIDOutput*) – Receives the output percentage
- **period** (*float or int*) – the loop time for doing calculations. This particularly effects calculations of the integral and differential terms. The default is 50ms.

**AbsoluteTolerance\_onTarget** (*value*)

**class PIDSourceType**

Bases: object

A description for the type of output value to provide to a *PIDController*

**kDisplacement = 0**

**kRate = 1**

`PIDController.PercentTolerance_onTarget` (*percentage*)

`PIDController.calculateFeedForward()`

Calculate the feed forward term

Both of the provided feed forward calculations are velocity feed forwards. If a different feed forward calculation is desired, the user can override this function and provide his or her own. This function does no synchronization because the `PIDController` class only calls it in synchronized code, so be careful if calling it oneself.

If a velocity PID controller is being used, the F term should be set to 1 over the maximum setpoint for the output. If a position PID controller is being used, the F term should be set to 1 over the maximum speed for the output measured in setpoint units per this controller's update period (see the default period in this class's constructor).

`PIDController.disable()`

Stop running the `PIDController`, this sets the output to zero before stopping.

`PIDController.enable()`

Begin running the `PIDController`.

`PIDController.free()`

Free the PID object

`PIDController.get()`

Return the current PID result. This is always centered on zero and constrained the the max and min outs.

**Returns** the latest calculated output

`PIDController.getAvgError()`

Returns the current difference of the error over the past few iterations. You can specify the number of

iterations to average with `setToleranceBuffer()` (defaults to 1). `getAvgError()` is used for the `onTarget()` function.

**Returns** the current average of the error

`PIDController.getD()`

Get the Differential coefficient.

**Returns** differential coefficient

`PIDController.getDeltaSetpoint()`

Returns the change in setpoint over time of the PIDController

**Returns** the change in setpoint over time

`PIDController.getError()`

Returns the current difference of the input from the setpoint.

**Returns** the current error

`PIDController.getF()`

Get the Feed forward coefficient.

**Returns** feed forward coefficient

`PIDController.getI()`

Get the Integral coefficient

**Returns** integral coefficient

`PIDController.getP()`

Get the Proportional coefficient.

**Returns** proportional coefficient

`PIDController.getPIDSourceType(pidSourceType)`

Returns the type of input the PID controller is using

**Returns** the PID controller input type

`PIDController.getSetpoint()`

Returns the current setpoint of the PIDController.

**Returns** the current setpoint

`PIDController.instances = 0`

`PIDController.isAvgErrorValid()`

Returns whether or not any values have been collected. If no values have been collected, `getAvgError` is 0, which is invalid.

**Returns** True if `getAvgError()` is currently valid.

`PIDController.isEnabled()`

Return True if PIDController is enabled.

`PIDController.kDefaultPeriod = 0.05`

`PIDController.onTarget()`

Return True if the error is within the percentage of the total input range, determined by `setTolerance`. This assumes that the maximum and minimum input were set using `setInput()`.

**Returns** True if the error is less than the tolerance

`PIDController.reset()`

Reset the previous error, the integral term, and disable the controller.

`PIDController.setAbsoluteTolerance` (*absvalue*)

Set the absolute error which is considered tolerable for use with `onTarget()`.

**Parameters** `absvalue` – absolute error which is tolerable in the units of the input object

`PIDController.setContinuous` (*continuous=True*)

Set the PID controller to consider the input to be continuous. Rather than using the max and min in as constraints, it considers them to be the same point and automatically calculates the shortest route to the setpoint.

**Parameters** `continuous` – Set to True turns on continuous, False turns off continuous

`PIDController.setInputRange` (*minimumInput, maximumInput*)

Sets the maximum and minimum values expected from the input.

**Parameters**

- `minimumInput` – the minimum percentage expected from the input
- `maximumInput` – the maximum percentage expected from the output

`PIDController.setOutputRange` (*minimumOutput, maximumOutput*)

Sets the minimum and maximum values to write.

**Parameters**

- `minimumOutput` – the minimum percentage to write to the output
- `maximumOutput` – the maximum percentage to write to the output

`PIDController.setPID` (*p, i, d, f=0.0*)

Set the PID Controller gain parameters. Set the proportional, integral, and differential coefficients.

**Parameters**

- `p` – Proportional coefficient
- `i` – Integral coefficient
- `d` – Differential coefficient
- `f` – Feed forward coefficient (optional, default is 0.0)

`PIDController.setPIDSourceType` (*pidSourceType*)

Sets what type of input the PID controller will use

**Parameters** `pidSourceType` – the type of input

`PIDController.setPercentTolerance` (*percentage*)

Set the percentage error which is considered tolerable for use with `onTarget()`. (Input of 15.0 = 15 percent)

**Parameters** `percentage` – percent error which is tolerable

`PIDController.setSetpoint` (*setpoint*)

Set the setpoint for the PIDController.

**Parameters** `setpoint` – the desired setpoint

`PIDController.setTolerance` (*percent*)

Set the percentage error which is considered tolerable for use with `onTarget()`. (Input of 15.0 = 15 percent)

**Parameters** `percent` – error which is tolerable

Deprecated since version 2015.1: Use `setPercentTolerance()` or `setAbsoluteTolerance()` instead.

`PIDController.setToleranceBuffer` (*bufLength*)

Set the number of previous error samples to average for tolerancing. When determining whether a mechanism is on target, the user may want to use a rolling average of previous measurements instead of a precise position or velocity. This is useful for noisy sensors which return a few erroneous measurements when the mechanism is on target. However, the mechanism will not register as on target for at least the specified `bufLength` cycles.

**Parameters** `bufLength` (*int*) – Number of previous cycles to average.

## 1.4.40 PowerDistributionPanel

`class wpilib.PowerDistributionPanel` (*module=0*)

Bases: `wpilib.SensorBase`

Use to obtain voltage, current, temperature, power, and energy from the CAN PDP

`clearStickyFaults` ()

Clear all pdp sticky faults

`getCurrent` (*channel*)

Query the current of a single channel of the PDP

**Returns** The current of one of the PDP channels (channels 0-15) in Amperes

**Return type** float

`getTemperature` ()

Query the temperature of the PDP

**Returns** The temperature of the PDP in degrees Celsius

**Return type** float

`getTotalCurrent` ()

Query the current of all monitored PDP channels (0-15)

**Returns** The total current drawn from the PDP channels in Amperes

**Return type** float

`getTotalEnergy` ()

Query the total energy drawn from the monitored PDP channels

**Returns** The total energy drawn from the PDP channels in Joules

**Return type** float

`getTotalPower` ()

Query the total power drawn from the monitored PDP channels

**Returns** The total power drawn from the PDP channels in Watts

**Return type** float

`getVoltage` ()

Query the input voltage of the PDP

**Returns** The voltage of the PDP in volts

**Return type** float

`resetTotalEnergy` ()

Reset the total energy to 0

### 1.4.41 Preferences

**class** `wpilib.Preferences`

Bases: `object`

Provides a relatively simple way to save important values to the RoboRIO to access the next time the RoboRIO is booted.

This class loads and saves from a file inside the RoboRIO. The user can not access the file directly, but may modify values at specific fields which will then be saved to the file when `save()` is called.

This class is thread safe.

This will also interact with `networktables.NetworkTable` by creating a table called “Preferences” with all the key-value pairs. To save using `NetworkTable`, simply set the boolean at position `~SAVE~` to true. Also, if the value of any variable is `”` in the `NetworkTable`, then that represents non-existence in the `Preferences` table.

Creates a preference class that will automatically read the file in a different thread. Any call to its methods will be blocked until the thread is finished reading.

**FILE\_NAME** = `’/home/lvuser/wpilib-preferences.ini’`

**NEW\_LINE** = `’\n’`

**SAVE\_FIELD** = `’~SAVE~’`

**TABLE\_NAME** = `’Preferences’`

**VALUE\_PREFIX** = `’=’`

**VALUE\_SUFFIX** = `”\n’`

**containsKey** (*key*)

Returns whether or not there is a key with the given name.

**Parameters** **key** – the key

**Returns** True if there is a value at the given key

**get** (*key, d=None*)

Returns the value at the given key.

**Parameters**

- **key** – the key
- **d** – the return value if the key doesn’t exist (default is None)

**Returns** the value (or d/None if none exists)

**getBoolean** (*key, backup*)

Returns the boolean at the given key. If this table does not have a value for that position, then the given backup value will be returned.

**Parameters**

- **key** – the key
- **backup** – the value to return if none exists in the table

**Returns** either the value in the table, or the backup

**Raises** `ValueError` if value cannot be converted to integer

**getFloat** (*key, backup*)

Returns the float at the given key. If this table does not have a value for that position, then the given backup value will be returned.

**Parameters**

- **key** – the key
- **backup** – the value to return if none exists in the table

**Returns** either the value in the table, or the backup

**Raises** ValueError if value cannot be converted to integer

**static getInstance** ()

Returns the preferences instance.

**Returns** the preferences instance

**getInt** (*key, backup*)

Returns the int at the given key. If this table does not have a value for that position, then the given backup value will be returned.

**Parameters**

- **key** – the key
- **backup** – the value to return if none exists in the table

**Returns** either the value in the table, or the backup

**Raises** ValueError if value cannot be converted to integer

**getKeys** ()

**Returns** a list of the keys

**getString** (*key, backup*)

Returns the string at the given key. If this table does not have a value for that position, then the given backup value will be returned.

**Parameters**

- **key** – the key
- **backup** – the value to return if none exists in the table

**Returns** either the value in the table, or the backup

**has\_key** (*key*)

Python style contains key.

**keys** ()

Python style get list of keys.

**put** (*key, value*)

Puts the given value into the given key position

**Parameters**

- **key** – the key
- **value** – the value

**putBoolean** (*key, value*)

Puts the given float into the preferences table.

The key may not have any whitespace nor an equals sign.

This will NOT save the value to memory between power cycles, to do that you must call `save()` (which must be used with care) at some point after calling this.



**Parameters**

- **key** – the key
- **value** – the value

**putFloat** (*key, value*)

Puts the given float into the preferences table.

The key may not have any whitespace nor an equals sign.

This will NOT save the value to memory between power cycles, to do that you must call `save()` (which must be used with care) at some point after calling this.

**Parameters**

- **key** – the key
- **value** – the value

**putInt** (*key, value*)

Puts the given int into the preferences table.

The key may not have any whitespace nor an equals sign.

This will NOT save the value to memory between power cycles, to do that you must call `save()` (which must be used with care) at some point after calling this.

**Parameters**

- **key** – the key
- **value** – the value

**putString** (*key, value*)

Puts the given string into the preferences table.

The value may not have quotation marks, nor may the key have any whitespace nor an equals sign.

This will NOT save the value to memory between power cycles, to do that you must call `save()` (which must be used with care) at some point after calling this.

**Parameters**

- **key** – the key
- **value** – the value

**read()**

The internal method to read from a file. This will be called in its own thread when the preferences singleton is first created.

**remove** (*key*)

Remove a preference

**Parameters** **key** – the key**save()**

Saves the preferences to a file on the RoboRIO.

This should NOT be called often. Too many writes can damage the RoboRIO's flash memory. While it is ok to save once or twice a match, this should never be called every run of `IterativeRobot.teleopPeriodic()`.

The actual writing of the file is done in a separate thread. However, any call to a get or put method will wait until the table is fully saved before continuing.

## 1.4.42 PWM

**class** `wpiplib.PWM(channel)`

Bases: `wpiplib.LiveWindowSendable`

Raw interface to PWM generation in the FPGA.

The values supplied as arguments for PWM outputs range from -1.0 to 1.0. They are mapped to the hardware dependent values, in this case 0-2000 for the FPGA. Changes are immediately sent to the FPGA, and the update occurs at the next FPGA cycle. There is no delay.

As of revision 0.1.10 of the FPGA, the FPGA interprets the 0-2000 values as follows:

- 2000 = full “forward”
- 1999 to 1001 = linear scaling from “full forward” to “center”
- 1000 = center value
- 999 to 2 = linear scaling from “center” to “full reverse”
- 1 = minimum pulse width (currently .5ms)
- 0 = disabled (i.e. PWM output is held low)

`kDefaultPwmPeriod` is the 1x period (5.05 ms). In hardware, the period scaling is implemented as an output squelch to get longer periods for old devices.

- 20ms periods (50 Hz) are the “safest” setting in that this works for all devices
- 20ms periods seem to be desirable for Vex Motors
- 20ms periods are the specified period for HS-322HD servos, but work reliably down to 10.0 ms; starting at about 8.5ms, the servo sometimes hums and get hot; by 5.0ms the hum is nearly continuous
- 10ms periods work well for Victor 884
- 5ms periods allows higher update rates for Luminary Micro Jaguar speed controllers. Due to the shipping firmware on the Jaguar, we can’t run the update period less than 5.05 ms.

Allocate a PWM given a channel.

**Parameters** `channel` (*int*) – The PWM channel number. 0-9 are on-board, 10-19 are on the MXP port

**class** `PeriodMultiplier`

Bases: `object`

Represents the amount to multiply the minimum servo-pulse pwm period by.

**k1X = 1**

**k2X = 2**

**k4X = 4**

`PWM.enableDeadbandElimination(eliminateDeadband)`

Optionally eliminate the deadband from a speed controller.

**Parameters** `eliminateDeadband` (*bool*) – If True, set the motor curve on the Jaguar to eliminate the deadband in the middle of the range. Otherwise, keep the full range without modifying any values.

`PWM.free()`

Free the PWM channel.

Free the resource associated with the PWM channel and set the value to 0.

PWM.**getCenterPwm** ()

PWM.**getChannel** ()

Gets the channel number associated with the PWM Object.

**Returns** The channel number.

**Return type** int

PWM.**getFullRangeScaleFactor** ()

Get the scale for positions.

PWM.**getMaxNegativePwm** ()

PWM.**getMaxPositivePwm** ()

PWM.**getMinNegativePwm** ()

PWM.**getMinPositivePwm** ()

PWM.**getNegativeScaleFactor** ()

Get the scale for negative speeds.

PWM.**getPosition** ()

Get the PWM value in terms of a position.

This is intended to be used by servos.

---

**Note:** `setBounds ()` must be called first.

---

**Returns** The position the servo is set to between 0.0 and 1.0.

**Return type** float

PWM.**getPositiveScaleFactor** ()

Get the scale for positive speeds.

PWM.**getRaw** ()

Get the PWM value directly from the hardware.

Read a raw value from a PWM channel.

**Returns** Raw PWM control value. Range: 0 - 255.

**Return type** int

PWM.**getSpeed** ()

Get the PWM value in terms of speed.

This is intended to be used by speed controllers.

---

**Note:** `setBounds ()` must be called first.

---

**Returns** The most recently set speed between -1.0 and 1.0.

**Return type** float

PWM.**kDefaultPwmCenter = 1.5**

the PWM range center in ms

PWM.**kDefaultPwmPeriod** = 5.05  
the default PWM period measured in ms.

PWM.**kDefaultPwmStepsDown** = 1000  
the number of PWM steps below the centerpoint

PWM.**kPwmDisabled** = 0  
the value to use to disable

PWM.**port**

PWM.**setBounds** (*max*, *deadbandMax*, *center*, *deadbandMin*, *min*)  
Set the bounds on the PWM pulse widths.

This sets the bounds on the PWM values for a particular type of controller. The values determine the upper and lower speeds as well as the deadband bracket.

**Parameters**

- **max** (*float*) – The max PWM pulse width in ms
- **deadbandMax** (*float*) – The high end of the deadband range pulse width in ms
- **center** (*float*) – The center (off) pulse width in ms
- **deadbandMin** (*float*) – The low end of the deadband pulse width in ms
- **min** (*float*) – The minimum pulse width in ms

PWM.**setPeriodMultiplier** (*mult*)  
Slow down the PWM signal for old devices.

**Parameters** **mult** (PWM.*PeriodMultiplier*) – The period multiplier to apply to this channel

PWM.**setPosition** (*pos*)  
Set the PWM value based on a position.

This is intended to be used by servos.

---

**Note:** *setBounds()* must be called first.

---

**Parameters** **pos** (*float*) – The position to set the servo between 0.0 and 1.0.

PWM.**setRaw** (*value*)  
Set the PWM value directly to the hardware.

Write a raw value to a PWM channel.

**Parameters** **value** (*int*) – Raw PWM value. Range 0 - 255.

PWM.**setSpeed** (*speed*)  
Set the PWM value based on a speed.

This is intended to be used by speed controllers.

---

**Note:** *setBounds()* must be called first.

---

**Parameters** **speed** (*float*) – The speed to set the speed controller between -1.0 and 1.0.

PWM.**setZeroLatch**()

### 1.4.43 Relay

**class** `wpiLib.Relay` (*channel*, *direction=None*)

Bases: `wpiLib.SensorBase`, `wpiLib.LiveWindowSendable`, `wpiLib.MotorSafety`

Controls VEX Robotics Spike style relay outputs.

Relays are intended to be connected to Spikes or similar relays. The relay channels controls a pair of pins that are either both off, one on, the other on, or both on. This translates into two Spike outputs at 0v, one at 12v and one at 0v, one at 0v and the other at 12v, or two Spike outputs at 12V. This allows off, full forward, or full reverse control of motors without variable speed. It also allows the two channels (forward and reverse) to be used independently for something that does not care about voltage polarity (like a solenoid).

Relay constructor given a channel.

Initially the relay is set to both lines at 0v.

#### Parameters

- **channel** (*int*) – The channel number for this relay (0-3)
- **direction** (*Relay.Direction*) – The direction that the Relay object will control. If not specified, defaults to allowing both directions.

**class** `Direction`

Bases: `object`

The Direction(s) that a relay is configured to operate in.

**kBoth = 0**

Both directions are valid

**kForward = 1**

Only forward is valid

**kReverse = 2**

Only reverse is valid

**class** `Relay.Value`

Bases: `object`

The state to drive a Relay to.

**kForward = 2**

Forward

**kOff = 0**

Off

**kOn = 1**

On for relays with defined direction

**kReverse = 3**

Reverse

`Relay.free`()

`Relay.get`()

Get the Relay State

Gets the current state of the relay.

When set to `kForwardOnly` or `kReverseOnly`, value is returned as `kOn/kOff` not `kForward/kReverse` (per the recommendation in Set)

**Returns** The current state of the relay

**Return type** `Relay.Value`

`Relay.getChannel()`

Get the channel number.

**Returns** The channel number.

`Relay.getDescription()`

`Relay.port`

`Relay.relayChannels = <wpilib.resource.Resource object>`

`Relay.set(value)`

Set the relay state.

Valid values depend on which directions of the relay are controlled by the object.

When set to `kBothDirections`, the relay can be set to any of the four states: `0v-0v`, `12v-0v`, `0v-12v`, `12v-12v`

When set to `kForwardOnly` or `kReverseOnly`, you can specify the constant for the direction or you can simply specify `kOff` and `kOn`. Using only `kOff` and `kOn` is recommended.

**Parameters** `value` (`Relay.Value`) – The state to set the relay.

`Relay.setDirection(direction)`

Set the Relay Direction.

Changes which values the relay can be set to depending on which direction is used.

Valid inputs are `kBothDirections`, `kForwardOnly`, and `kReverseOnly`.

**Parameters** `direction` (`Relay.Direction`) – The direction for the relay to operate in

`Relay.stopMotor()`

## 1.4.44 Resource

`class wpilib.Resource(size)`

Bases: `object`

Tracks resources in the program.

The Resource class is a convenient way of keeping track of allocated arbitrary resources in the program. Resources are just indices that have an lower and upper bound that are tracked by this class. In the library they are used for tracking allocation of hardware channels but this is purely arbitrary. The resource class does not do any actual allocation, but simply tracks if a given index is currently in use.

Allocate storage for a new instance of Resource. Allocate a bool array of values that will get initialized to indicate that no resources have been allocated yet. The indices of the resources are `0..size-1`.

**Parameters** `size` – The number of blocks to allocate

`allocate(obj, index=None)`

Allocate a resource.

When `index` is `None` or unspecified, a free resource value within the range is located and returned after it is marked allocated. Otherwise, it is verified unallocated, then returned.

**Parameters**

- **obj** – The object requesting the resource.
- **index** – The resource to allocate

**Returns** The index of the allocated block.

**Raises `IndexError`** – If there are no resources available to be allocated or the specified index is already used.

**free** (*index*)

Force-free an allocated resource. After a resource is no longer needed, for example a destructor is called for a channel assignment class, free will release the resource value so it can be reused somewhere else in the program.

**Parameters `index`** – The index of the resource to free.

### 1.4.45 RobotBase

**class** `wpilib.RobotBase`

Bases: `object`

Implement a Robot Program framework.

The `RobotBase` class is intended to be subclassed by a user creating a robot program. Overridden `autonomous()` and `operatorControl()` methods are called at the appropriate time as the match proceeds. In the current implementation, the Autonomous code will run to completion before the OperatorControl code could start. In the future the Autonomous code might be spawned as a task, then killed at the end of the Autonomous period.

User code should be placed in the constructor that runs before the Autonomous or Operator Control period starts. The constructor will run to completion before Autonomous is entered.

**Warning:** If you override `__init__` in your robot class, you must call the base class constructor. This must be used to ensure that the communications code starts.

**free** ()

Free the resources for a `RobotBase` class.

**static initializeHardwareConfiguration** ()

Common initialization for all robot programs.

**isAutonomous** ()

Determine if the robot is currently in Autonomous mode.

**Returns** True if the robot is currently operating Autonomously as determined by the field controls.

**Return type** `bool`

**isDisabled** ()

Determine if the Robot is currently disabled.

**Returns** True if the Robot is currently disabled by the field controls.

**Return type** `bool`

**isEnabled** ()

Determine if the Robot is currently enabled.

**Returns** True if the Robot is currently enabled by the field controls.

**Return type** `bool`

**isNewDataAvailable** ()

Indicates if new data is available from the driver station.

**Returns** Has new data arrived over the network since the last time this function was called?

**Return type** bool

**isOperatorControl** ()

Determine if the robot is currently in Operator Control mode.

**Returns** True if the robot is currently operating in Tele-Op mode as determined by the field controls.

**Return type** bool

**static isReal** ()

**Returns** If the robot is running in the real world.

**Return type** bool

**static isSimulation** ()

**Returns** If the robot is running in simulation.

**Return type** bool

**isTest** ()

Determine if the robot is currently in Test mode.

**Returns** True if the robot is currently operating in Test mode as determined by the driver station.

**Return type** bool

**static main** (*robot\_cls*)

Starting point for the applications.

**startCompetition** ()

Provide an alternate “main loop” via startCompetition().

## 1.4.46 RobotDrive

**class** `wpiplib.RobotDrive` (*\*args*, *\*\*kwargs*)

Bases: `wpiplib.MotorSafety`

Operations on a robot drivetrain based on a definition of the motor configuration.

The robot drive class handles basic driving for a robot. Currently, 2 and 4 motor tank and mecanum drive trains are supported. In the future other drive types like swerve might be implemented. Motor channel numbers are passed supplied on creation of the class. Those are used for either the drive function (intended for hand created drive code, such as autonomous) or with the Tank/Arcade functions intended to be used for Operator Control driving.

Constructor for RobotDrive.

Either 2 or 4 motors can be passed to the constructor to implement a two or four wheel drive system, respectively.

When positional arguments are used, these are the two accepted orders:

- leftMotor, rightMotor
- frontLeftMotor, rearLeftMotor, frontRightMotor, rearRightMotor



Alternatively, the above names can be used as keyword arguments.

Either channel numbers or motor controllers can be passed (determined by whether the passed object has a *set* function). If channel numbers are passed, the `motorController` keyword argument, if present, is the motor controller class to use; if unspecified, *Talon* is used.

#### class `MotorType`

Bases: `object`

The location of a motor on the robot for the purpose of driving.

**`kFrontLeft = 0`**

Front left

**`kFrontRight = 1`**

Front right

**`kRearLeft = 2`**

Rear left

**`kRearRight = 3`**

Rear right

`RobotDrive.arcadeDrive(*args, **kwargs)`

Provide tank steering using the stored robot configuration.

Either one or two joysticks (with optional specified axis) or two raw values may be passed positionally, along with an optional `squaredInputs` boolean. The valid positional combinations are:

- `stick`
- `stick, squaredInputs`
- `moveStick, moveAxis, rotateStick, rotateAxis`
- `moveStick, moveAxis, rotateStick, rotateAxis, squaredInputs`
- `moveValue, rotateValue`
- `moveValue, rotateValue, squaredInputs`

Alternatively, the above names can be used as keyword arguments. The behavior of mixes of keyword arguments in other than the combinations above is undefined.

If specified positionally, the value and joystick versions are disambiguated by looking for a *getY* function on the stick.

#### Parameters

- **`stick`** – The joystick to use for Arcade single-stick driving. The Y-axis will be selected for forwards/backwards and the X-axis will be selected for rotation rate.
- **`moveStick`** – The Joystick object that represents the forward/backward direction.
- **`moveAxis`** – The axis on the `moveStick` object to use for forwards/backwards (typically `Y_AXIS`).
- **`rotateStick`** – The Joystick object that represents the rotation value.
- **`rotateAxis`** – The axis on the rotation object to use for the rotate right/left (typically `X_AXIS`).
- **`moveValue`** – The value to use for forwards/backwards.
- **`rotateValue`** – The value to use for the rotate right/left.

- **squaredInputs** – Setting this parameter to True decreases the sensitivity at lower speeds. Defaults to True if unspecified.

RobotDrive.**drive** (*outputMagnitude, curve*)

Drive the motors at “outputMagnitude” and “curve”.

Both outputMagnitude and curve are -1.0 to +1.0 values, where 0.0 represents stopped and not turning. curve < 0 will turn left and curve > 0 will turn right.

The algorithm for steering provides a constant turn radius for any normal speed range, both forward and backward. Increasing m\_sensitivity causes sharper turns for fixed values of curve.

This function will most likely be used in an autonomous routine.

#### Parameters

- **outputMagnitude** – The speed setting for the outside wheel in a turn, forward or backwards, +1 to -1.
- **curve** – The rate of turn, constant for different forward speeds. Set curve < 0 for left turn or curve > 0 for right turn.

Set  $curve = e^{(-r/w)}$  to get a turn radius  $r$  for wheelbase  $w$  of your robot. Conversely, turn radius  $r = -\ln(curve)*w$  for a given value of curve and wheelbase  $w$ .

RobotDrive.**free** ()

RobotDrive.**getDescription** ()

RobotDrive.**getNumMotors** ()

RobotDrive.**holonomicDrive** (*magnitude, direction, rotation*)

Holonomic Drive method for Mecanum wheeled robots.

This is an alias to *mecanumDrive\_Polar()* for backward compatibility.

#### Parameters

- **magnitude** – The speed that the robot should drive in a given direction. [-1.0..1.0]
- **direction** – The direction the robot should drive. The direction and magnitude are independent of the rotation rate.
- **rotation** – The rate of rotation for the robot that is completely independent of the magnitude or direction. [-1.0..1.0]

RobotDrive.**kArcadeRatioCurve\_Reported** = False

RobotDrive.**kArcadeStandard\_Reported** = False

RobotDrive.**kDefaultExpirationTime** = 0.1

RobotDrive.**kDefaultMaxOutput** = 1.0

RobotDrive.**kDefaultSensitivity** = 0.5

RobotDrive.**kMaxNumberOfMotors** = 4

RobotDrive.**kMecanumCartesian\_Reported** = False

RobotDrive.**kMecanumPolar\_Reported** = False

RobotDrive.**kTank\_Reported** = False

**static** RobotDrive.**limit** (*num*)

Limit motor values to the -1.0 to +1.0 range.

`RobotDrive.mecanumDrive_Cartesian` (*x*, *y*, *rotation*, *gyroAngle*)

Drive method for Mecanum wheeled robots.

A method for driving with Mecanum wheeled robots. There are 4 wheels on the robot, arranged so that the front and back wheels are toed in 45 degrees. When looking at the wheels from the top, the roller axles should form an X across the robot.

This is designed to be directly driven by joystick axes.

#### Parameters

- **x** – The speed that the robot should drive in the X direction. [-1.0..1.0]
- **y** – The speed that the robot should drive in the Y direction. This input is inverted to match the forward == -1.0 that joysticks produce. [-1.0..1.0]
- **rotation** – The rate of rotation for the robot that is completely independent of the translation. [-1.0..1.0]
- **gyroAngle** – The current angle reading from the gyro. Use this to implement field-oriented controls.

`RobotDrive.mecanumDrive_Polar` (*magnitude*, *direction*, *rotation*)

Drive method for Mecanum wheeled robots.

A method for driving with Mecanum wheeled robots. There are 4 wheels on the robot, arranged so that the front and back wheels are toed in 45 degrees. When looking at the wheels from the top, the roller axles should form an X across the robot.

#### Parameters

- **magnitude** – The speed that the robot should drive in a given direction.
- **direction** – The direction the robot should drive in degrees. The direction and magnitude are independent of the rotation rate.
- **rotation** – The rate of rotation for the robot that is completely independent of the magnitude or direction. [-1.0..1.0]

**static** `RobotDrive.normalize` (*wheelSpeeds*)

Normalize all wheel speeds if the magnitude of any wheel is greater than 1.0.

**static** `RobotDrive.rotateVector` (*x*, *y*, *angle*)

Rotate a vector in Cartesian space.

`RobotDrive.setCANJaguarSyncGroup` (*syncGroup*)

Set the number of the sync group for the motor controllers. If the motor controllers are :class:`CANJaguar`s, then they will be added to this sync group, causing them to update their values at the same time.

**Parameters** **syncGroup** – The update group to add the motor controllers to.

`RobotDrive.setInvertedMotor` (*motor*, *isInverted*)

Invert a motor direction.

This is used when a motor should run in the opposite direction as the drive code would normally run it. Motors that are direct drive would be inverted, the drive code assumes that the motors are geared with one reversal.

#### Parameters

- **motor** – The motor index to invert.
- **isInverted** – True if the motor should be inverted when operated.

`RobotDrive.setLeftRightMotorOutputs` (*leftOutput*, *rightOutput*)

Set the speed of the right and left motors.

This is used once an appropriate drive setup function is called such as `twoWheelDrive()`. The motors are set to “leftSpeed” and “rightSpeed” and includes flipping the direction of one side for opposing motors.

**Parameters**

- **leftOutput** – The speed to send to the left side of the robot.
- **rightOutput** – The speed to send to the right side of the robot.

`RobotDrive.setMaxOutput` (*maxOutput*)

Configure the scaling factor for using `RobotDrive` with motor controllers in a mode other than `PercentVbus`.

**Parameters** **maxOutput** – Multiplied with the output percentage computed by the drive functions.

`RobotDrive.setSensitivity` (*sensitivity*)

Set the turning sensitivity.

This only impacts the `drive()` entry-point.

**Parameters** **sensitivity** – Effectively sets the turning sensitivity (or turn radius for a given value)

`RobotDrive.stopMotor` ()

`RobotDrive.tankDrive` (*\*args*, *\*\*kwargs*)

Provide tank steering using the stored robot configuration.

Either two joysticks (with optional specified axis) or two raw values may be passed positionally, along with an optional `squaredInputs` boolean. The valid positional combinations are:

- `leftStick`, `rightStick`
- `leftStick`, `rightStick`, `squaredInputs`
- `leftStick`, `leftAxis`, `rightStick`, `rightAxis`
- `leftStick`, `leftAxis`, `rightStick`, `rightAxis`, `squaredInputs`
- `leftValue`, `rightValue`
- `leftValue`, `rightValue`, `squaredInputs`

Alternatively, the above names can be used as keyword arguments. The behavior of mixes of keyword arguments in other than the combinations above is undefined.

If specified positionally, the value and joystick versions are disambiguated by looking for a `getY` function.

**Parameters**

- **leftStick** – The joystick to control the left side of the robot.
- **leftAxis** – The axis to select on the left side Joystick object (defaults to the Y axis if unspecified).
- **rightStick** – The joystick to control the right side of the robot.
- **rightAxis** – The axis to select on the right side Joystick object (defaults to the Y axis if unspecified).
- **leftValue** – The value to control the left side of the robot.
- **rightValue** – The value to control the right side of the robot.

- **squaredInputs** – Setting this parameter to True decreases the sensitivity at lower speeds. Defaults to True if unspecified.

### 1.4.47 RobotState

**class** `wpilib.RobotState`

Bases: `object`

Provides an interface to determine the current operating state of the robot code.

**impl** = `None`

**static** `isAutonomous()`

**static** `isDisabled()`

**static** `isEnabled()`

**static** `isOperatorControl()`

**static** `isTest()`

### 1.4.48 SafePWM

**class** `wpilib.SafePWM(channel)`

Bases: `wpilib.PWM`, `wpilib.MotorSafety`

A raw PWM interface that implements the `MotorSafety` interface

Constructor for a SafePWM object taking a channel number.

**Parameters** `channel` (*int*) – The channel number to be used for the underlying PWM object. 0-9 are on-board, 10-19 are on the MXP port.

**disable()**

**getDescription()**

**stopMotor()**

Stop the motor associated with this PWM object. This is called by the MotorSafety object when it has a timeout for this PWM and needs to stop it from running.

### 1.4.49 SampleRobot

**class** `wpilib.SampleRobot`

Bases: `wpilib.RobotBase`

A simple robot base class that knows the standard FRC competition states (disabled, autonomous, or operator controlled).

You can build a simple robot program off of this by overriding the `robotinit()`, `disabled()`, `autonomous()` and `operatorControl()` methods. The `startCompetition()` method will call these methods (sometimes repeatedly) depending on the state of the competition.

Alternatively you can override the `robotMain()` method and manage all aspects of the robot yourself (not recommended).

**Warning:** While it may look like a good choice to use for your code if you're inexperienced, don't. Unless you know what you are doing, complex code will be much more difficult under this system. Use *IterativeRobot* or command based instead if you're new.

**autonomous ()**

Autonomous should go here. Users should add autonomous code to this method that should run while the field is in the autonomous period.

Called once each time the robot enters the autonomous state.

**disabled ()**

Disabled should go here. Users should overload this method to run code that should run while the field is disabled.

Called once each time the robot enters the disabled state.

**logger = <logging.Logger object>**

A python logging object that you can use to send messages to the log. It is recommended to use this instead of print statements.

**operatorControl ()**

Operator control (tele-operated) code should go here. Users should add Operator Control code to this method that should run while the field is in the Operator Control (tele-operated) period.

Called once each time the robot enters the operator-controlled state.

**robotInit ()**

Robot-wide initialization code should go here.

Users should override this method for default Robot-wide initialization which will be called when the robot is first powered on. It will be called exactly 1 time.

---

**Note:** It is simpler to override this function instead of defining a constructor for your robot class

---

**Warning:** the Driver Station "Robot Code" light and FMS "Robot Ready" indicators will be off until RobotInit() exits. Code in `robotInit()` that waits for enable will cause the robot to never indicate that the code is ready, causing the robot to be bypassed in a match.

**robotMain ()**

Robot main program for free-form programs.

This should be overridden by user subclasses if the intent is to not use the `autonomous()` and `operatorControl()` methods. In that case, the program is responsible for sensing when to run the autonomous and operator control functions in their program.

This method will be called immediately after the constructor is called. If it has not been overridden by a user subclass (i.e. the default version runs), then the `robotInit()`, `disabled()`, `autonomous()` and `operatorControl()` methods will be called.

If you override this function, you must call `hal.HALNetworkCommunicationObserveUserProgramStarting()` to indicate that your robot is ready to be enabled, as it will not be called for you.

**Warning:** Nobody actually wants to override this function. Neither do you.

**startCompetition ()**

Start a competition. This code tracks the order of the field starting to ensure that everything happens in the right order. Repeatedly run the correct method, either `Autonomous` or `OperatorControl` when the robot is

enabled. After running the correct method, wait for some state to change, either the other mode starts or the robot is disabled. Then go back and wait for the robot to be enabled again.

**test ()**

Test code should go here. Users should add test code to this method that should run while the robot is in test mode.

## 1.4.50 SD540

**class** `wpiplib.SD540` (*channel*)

Bases: `wpiplib.SafePWM`

Mindsensors SD540 Speed Controller

Constructor.

**Parameters** `channel` – The PWM channel that the SD540 is attached to. 0-9 are on-board, 10-19 are on the MXP port

---

**Note:** Note that the SD540 uses the following bounds for PWM values. These values should work reasonably well for most controllers, but if users experience issues such as asymmetric behavior around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the SD540 User Manual available from Mindsensors.

- 2.05ms = full “forward”
  - 1.55ms = the “high end” of the deadband range
  - 1.50ms = center of the deadband range (off)
  - 1.44ms = the “low end” of the deadband range
  - .94ms = full “reverse”
- 

**free ()**

**get ()**

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted ()**

Common interface for inverting the direction of a speed controller.

**Returns** The state of inversion (True is inverted)

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the `PIDController`.

**set** (*speed*, *syncGroup=0*)

Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- `speed` (*float*) – The speed to set. Value should be between -1.0 and 1.0.

- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting the direction of a speed controller.

**Parameters** **isInverted** – The state of inversion (True is inverted).

### 1.4.51 Sendable

**class** `wplib.Sendable`

Bases: `object`

The base interface for objects that can be sent over the network through network tables

### 1.4.52 SendableChooser

**class** `wplib.SendableChooser`

Bases: `wplib.Sendable`

A useful tool for presenting a selection of options to be displayed on the SmartDashboard

For instance, you may wish to be able to select between multiple autonomous modes. You can do this by putting every possible Command you want to run as an autonomous into a SendableChooser and then put it into the SmartDashboard to have a list of options appear on the laptop. Once autonomous starts, simply ask the SendableChooser what the selected value is.

Example:

```
# This shows the user two options on the SmartDashboard
chooser = wplib.SendableChooser()
chooser.addObject('option1', '1')
chooser.addObject('option2', '2')

wplib.SmartDashboard.putData('Choice', chooser)

# .. later, ask to see what the user selected?
value = chooser.getSelected()
```

Instantiates a SendableChooser.

**DEFAULT** = 'default'

**OPTIONS** = 'options'

**SELECTED** = 'selected'

**addDefault** (*name, object*)

Add the given object to the list of options and marks it as the default. Functionally, this is very close to `addObject(...)` except that it will use this as the default option if none other is explicitly selected.

**Parameters**

- **name** – the name of the option
- **object** – the option

**addObject** (*name, object*)

Adds the given object to the list of options. On the SmartDashboard on the desktop, the object will appear as the given name.



**Parameters**

- **name** – the name of the option
- **object** – the option

**getSelected()**

Returns the object associated with the selected option. If there is none selected, it will return the default. If there is none selected and no default, then it will return None.

**Returns** the object associated with the selected option

## 1.4.53 SensorBase

**class** `wpiplib.SensorBase`

Bases: `wpiplib.LiveWindowSendable`

Base class for all sensors

Stores most recent status information as well as containing utility functions for checking channels and error processing.

**static checkAnalogInputChannel** (*channel*)

Check that the analog input number is value. Verify that the analog input number is one of the legal channel numbers. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkAnalogOutputChannel** (*channel*)

Check that the analog input number is value. Verify that the analog input number is one of the legal channel numbers. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkDigitalChannel** (*channel*)

Check that the digital channel number is valid. Verify that the channel number is one of the legal channel numbers. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkPDPChannel** (*channel*)

Verify that the power distribution channel number is within limits. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkPDPModule** (*module*)

Verify that the power distribution module number is within limits. Module numbers are 0-based.

**Parameters** **module** – The module number to check.

**static checkPWMChannel** (*channel*)

Check that the digital channel number is valid. Verify that the channel number is one of the legal channel numbers. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkRelayChannel** (*channel*)

Check that the digital channel number is valid. Verify that the channel number is one of the legal channel numbers. Channel numbers are 0-based.

**Parameters** **channel** – The channel number to check.

**static checkSolenoidChannel** (*channel*)

Verify that the solenoid channel number is within limits. Channel numbers are 0-based.

**Parameters** `channel` – The channel number to check.

**static** `checkSolenoidModule (moduleNumber)`

Verify that the solenoid module is correct.

**Parameters** `moduleNumber` – The solenoid module number to check.

**defaultSolenoidModule = 0**

Default solenoid module

**free ()**

Free the resources used by this object

**static** `getDefaultSolenoidModule ()`

Get the number of the default solenoid module.

**Returns** The number of the default solenoid module.

**kAnalogInputChannels = 8**

Number of analog input channels

**kAnalogOutputChannels = 2**

Number of analog output channels

**kDigitalChannels = 26**

Number of digital channels per roboRIO

**kPDPChannels = 16**

Number of power distribution channels

**kPDPModules = 63**

Number of power distribution channels

**kPwmChannels = 20**

Number of PWM channels per roboRIO

**kRelayChannels = 4**

Number of relay channels per roboRIO

**kSolenoidChannels = 8**

Number of solenoid channels per module

**kSolenoidModules = 2**

Number of solenoid modules

**kSystemClockTicksPerMicrosecond = 40**

Ticks per microsecond

**static** `setDefaultSolenoidModule (moduleNumber)`

Set the default location for the Solenoid module.

**Parameters** `moduleNumber` – The number of the solenoid module to use.

### 1.4.54 Servo

**class** `wpiplib.Servo (channel)`

Bases: `wpiplib.PWM`

Standard hobby style servo

The range parameters default to the appropriate values for the Hitec HS-322HD servo provided in the FIRST Kit of Parts in 2008.

Constructor.

- By default `kDefaultMaxServoPWM` ms is used as the maxPWM value
- By default `kDefaultMinServoPWM` ms is used as the minPWM value

**Parameters** `channel` (*int*) – The PWM channel to which the servo is attached. 0-9 are on-board, 10-19 are on the MXP port.

**free** ()

**get** ()

Get the servo position.

Servo values range from 0.0 to 1.0 corresponding to the range of full left to full right.

**Returns** Position from 0.0 to 1.0.

**Return type** float

**getAngle** ()

Get the servo angle.

Assume that the servo angle is linear with respect to the PWM value (big assumption, need to test).

**Returns** The angle in degrees to which the servo is set.

**Return type** float

**getServoAngleRange** ()

**kDefaultMaxServoPWM** = 2.4

**kDefaultMinServoPWM** = 0.6

**kMaxServoAngle** = 180.0

**kMinServoAngle** = 0.0

**set** (*value*)

Set the servo position.

Servo values range from 0.0 to 1.0 corresponding to the range of full left to full right.

**Parameters** `value` (*float*) – Position from 0.0 to 1.0.

**setAngle** (*degrees*)

Set the servo angle.

Assumes that the servo angle is linear with respect to the PWM value (big assumption, need to test).

Servo angles that are out of the supported range of the servo simply “saturate” in that direction. In other words, if the servo has a range of (X degrees to Y degrees) then angles of less than X result in an angle of X being set and angles of more than Y degrees result in an angle of Y being set.

**Parameters** `degrees` (*float*) – The angle in degrees to set the servo.

### 1.4.55 SmartDashboard

**class** `wpiilib.SmartDashboard`

Bases: `object`

The bridge between robot programs and the SmartDashboard on the laptop

When a value is put into the SmartDashboard, it pops up on the SmartDashboard on the remote host. Users can put values into and get values from the SmartDashboard.

These values can also be accessed by a NetworkTables client via the 'SmartDashboard' table:

```
from networktables import NetworkTable
sd = NetworkTable.getTable('SmartDashboard')

# sd.putXXX and sd.getXXX work as expected here
```

**static getBoolean** (*key*, *defaultValue*=<class 'wpilib.smartdashboard.SmartDashboard.\_defaultValueSentry'>)  
Returns the value at the specified key.

**Parameters**

- **key** (*str*) – the key
- **defaultValue** – returned if the key doesn't exist

**Returns** the value

**Raises** `KeyError` if the key doesn't exist and *defaultValue* is not provided.

**static getData** (*key*)

Returns the value at the specified key.

**Parameters** **key** (*str*) – the key

**Returns** the value

**Raises** `KeyError` if the key doesn't exist

**static getDouble** (*key*, *defaultValue*=<class 'wpilib.smartdashboard.SmartDashboard.\_defaultValueSentry'>)

Returns the value at the specified key.

**Parameters**

- **key** (*str*) – the key
- **defaultValue** – returned if the key doesn't exist

**Return type** float

**Raises** `KeyError` if the key doesn't exist and *defaultValue* is not provided.

**static getInt** (*key*, *defaultValue*=<class 'wpilib.smartdashboard.SmartDashboard.\_defaultValueSentry'>)

Returns the value at the specified key.

**Parameters**

- **key** (*str*) – the key
- **defaultValue** – returned if the key doesn't exist

**Return type** float

**Raises** `KeyError` if the key doesn't exist and *defaultValue* is not provided.

**static getNumber** (*key*, *defaultValue*=<class 'wpilib.smartdashboard.SmartDashboard.\_defaultValueSentry'>)

Returns the value at the specified key.

**Parameters**

- **key** (*str*) – the key
- **defaultValue** – returned if the key doesn't exist

**Return type** float

**Raises** `KeyError` if the key doesn't exist and *defaultValue* is not provided.

**static getString** (*key*, *defaultValue*=<class 'wpilib.smartdashboard.SmartDashboard.\_defaultValueSentry'>)  
Returns the value at the specified key.

**Parameters**

- **key** (*str*) – the key
- **defaultValue** – returned if the key doesn't exist

**Return type** *str*

**Raises** *KeyError* if the key doesn't exist and *defaultValue* is not provided.

**static putBoolean** (*key*, *value*)

Maps the specified key to the specified value in this table. The key can not be None.

The value can be retrieved by calling the get method with a key that is equal to the original key.

**Parameters**

- **key** (*str*) – the key
- **value** – the value

**static putData** (*\*args*, *\*\*kwargs*)

Maps the specified key to the specified value in this table. The value can be retrieved by calling the get method with a key that is equal to the original key.

Two argument formats are supported: key, data:

**Parameters**

- **key** (*str*) – the key (cannot be None)
- **data** – the value

Or the single argument “value”:

**Parameters** **value** – the named value (getName is called to retrieve the value)

**static putDouble** (*key*, *value*)

Maps the specified key to the specified value in this table. The key can not be None. The value can be retrieved by calling the get method with a key that is equal to the original key.

**Parameters**

- **key** (*str*) – the key
- **value** (*int or float*) – the value

**static putInt** (*key*, *value*)

Maps the specified key to the specified value in this table. The key can not be None. The value can be retrieved by calling the get method with a key that is equal to the original key.

**Parameters**

- **key** (*str*) – the key
- **value** (*int or float*) – the value

**static putNumber** (*key*, *value*)

Maps the specified key to the specified value in this table. The key can not be None. The value can be retrieved by calling the get method with a key that is equal to the original key.

**Parameters**

- **key** (*str*) – the key

- **value** (*int or float*) – the value

**static putString** (*key, value*)

Maps the specified key to the specified value in this table. The key can not be None. The value can be retrieved by calling the get method with a key that is equal to the original key.

#### Parameters

- **key** (*str*) – the key
- **value** (*str*) – the value

**table** = None

**tablesToData** = {}

## 1.4.56 Solenoid

**class** `wpiplib.Solenoid` (*\*args, \*\*kwargs*)

Bases: `wpiplib.SolenoidBase`

Solenoid class for running high voltage Digital Output.

The Solenoid class is typically used for pneumatics solenoids, but could be used for any device within the current spec of the PCM.

Constructor.

Arguments can be supplied as positional or keyword. Acceptable positional argument combinations are:

- **channel**
- **moduleNumber, channel**

Alternatively, the above names can be used as keyword arguments.

#### Parameters

- **moduleNumber** (*int*) – The CAN ID of the PCM the solenoid is attached to
- **channel** (*int*) – The channel on the PCM to control (0..7)

**free** ()

Mark the solenoid as freed.

**get** ()

Read the current value of the solenoid.

**Returns** The current value of the solenoid.

**Return type** bool

**isBlackListed** ()

**Check if the solenoid is blacklisted.** If a solenoid is shorted, it is added to the blacklist and disabled until power cycle, or until faults are cleared. See `clearAllPCMStickyFaults` ()

**Returns** If solenoid is disabled due to short.

**port**

**set** (*on*)

Set the value of a solenoid.

**Parameters** **on** (*bool*) – Turn the solenoid output off or on.

### 1.4.57 SolenoidBase

`class wpilib.SolenoidBase(moduleNumber)`

Bases: `wpilib.SensorBase`

SolenoidBase class is the common base class for the Solenoid and DoubleSolenoid classes.

Constructor.

**Parameters** `moduleNumber` – The PCM CAN ID

`all_allocated = {}`

`all_mutex = {}`

`all_ports = {}`

`clearAllPCMStickyFaults()`

Clear ALL sticky faults inside the PCM that Solenoid is wired to.

**If a sticky fault is set, then it will be persistently cleared. Compressor drive** maybe momentarily disable while flages are being cleared. Care should be taken to not call this too frequently, otherwise normal compressor functionality may be prevented.

If no sticky faults are set then this call will have no effect.

`getAll()`

Read all 8 solenoids from the module used by this solenoid as a single byte.

**Returns** The current value of all 8 solenoids on this module.

`getPCMSolenoidBlackList()`

**Reads complete solenoid blacklist for all 8 solenoids as a single byte.** If a solenoid is shorted, it is added to the blacklist and disabled until power cycle, or until faults are cleared. See `clearAllPCMStickyFaults()`

**Returns** The solenoid blacklist of all 8 solenoids on the module.

`getPCMSolenoidVoltageFault()`

**Returns** True if PCM is in fault state : The common highside solenoid voltage rail is too low, most likely a solenoid channel has been shorted.

`getPCMSolenoidVoltageStickyFault()`

**Returns** True if PCM Sticky fault is set : The common highside solenoid voltage rail is too low, most likely a solenoid channel has been shorted.

`set(value, mask)`

Set the value of a solenoid.

**Parameters**

- **value** – The value you want to set on the module.
- **mask** – The channels you want to be affected.

### 1.4.58 Spark

`class wpilib.Spark(channel)`

Bases: `wpilib.SafePWM`

REV Robotics SPARK Speed Controller

Constructor.

**Parameters** `channel` – The PWM channel that the SPARK is attached to. 0-9 are on-board, 10-19 are on the MXP port

---

**Note:** Note that the SD540 uses the following bounds for PWM values. These values should work reasonably well for most controllers, but if users experience issues such as asymmetric behavior around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the SD540 User Manual available from Mindsensors.

- 2.003ms = full “forward”
  - 1.55ms = the “high end” of the deadband range
  - 1.50ms = center of the deadband range (off)
  - 1.46ms = the “low end” of the deadband range
  - .999ms = full “reverse”
- 

**free** ()

**get** ()

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted** ()

Common interface for inverting the direction of a speed controller.

**Returns** The state of inversion (True is inverted)

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the PIDController.

**set** (*speed*, *syncGroup=0*)

Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting the direction of a speed controller.

**Parameters** `isInverted` – The state of inversion (True is inverted).

### 1.4.59 SPI

**class** `wpilib.SPI` (*port*, *simPort=None*)

Bases: object



Represents a SPI bus port

Example usage:

```
spi = wpilib.SPI(wpilib.SPI.Port.kOnboardCS0)

# Write bytes 'text', and receive something
data = spi.transaction(b'text')
```

Constructor

#### Parameters

- **port** (*SPI.Port*) – the physical SPI port
- **simPort** – This must be an object that implements all of the spi\* functions from hal\_impl that you use. See `test_spi.py` for an example.

**class Port**

Bases: object

**kMXP = 4**

**kOnboardCS0 = 0**

**kOnboardCS1 = 1**

**kOnboardCS2 = 2**

**kOnboardCS3 = 3**

**SPI.devices = 0**

**SPI.free()**

**SPI.freeAccumulator()**

Frees the accumulator.

**SPI.getAccumulatorAverage()**

Read the average of the accumulated value.

**Returns** The accumulated average value (value / count).

**SPI.getAccumulatorCount()**

Read the number of accumulated values.

Read the count of the accumulated values since the accumulator was last Reset().

**Returns** The number of times samples from the channel were accumulated.

**SPI.getAccumulatorLastValue()**

Read the last value read by the accumulator engine.

**SPI.getAccumulatorOutput()**

Read the accumulated value and the number of accumulated values atomically.

This function reads the value and count atomically. This can be used for averaging.

**Returns** tuple of (value, count)

**SPI.getAccumulatorValue()**

Read the accumulated value.

**Returns** The 64-bit value accumulated since the last Reset().

`SPI.initAccumulator` (*period, cmd, xfer\_size, valid\_mask, valid\_value, data\_shift, data\_size, is\_signed, big\_endian*)

Initialize the accumulator.

**Parameters**

- **period** – Time between reads
- **cmd** – SPI command to send to request data
- **xfer\_size** – SPI transfer size, in bytes
- **valid\_mask** – Mask to apply to received data for validity checking
- **valid\_data** – After `valid_mask` is applied, required matching value for validity checking
- **data\_shift** – Bit shift to apply to received data to get actual data value
- **data\_size** – Size (in bits) of data field
- **is\_signed** – Is data field signed?
- **big\_endian** – Is device big endian?

`SPI.port`

`SPI.read` (*initiate, size*)

Read a word from the receive FIFO.

Waits for the current transfer to complete if the receive FIFO is empty.

If the receive FIFO is empty, there is no active transfer, and `initiate` is `False`, errors.

**Parameters**

- **initiate** – If `True`, this function pushes “0” into the transmit buffer and initiates a transfer. If `False`, this function assumes that data is already in the receive FIFO from a previous write.
- **size** – Number of bytes to read.

**Returns** received data bytes

`SPI.resetAccumulator` ()

Resets the accumulator to zero.

`SPI.setAccumulatorCenter` (*center*)

Set the center value of the accumulator.

The center value is subtracted from each value before it is added to the accumulator. This is used for the center value of devices like gyros and accelerometers to make integration work and to take the device offset into account when integrating.

`SPI.setAccumulatorDeadband` (*deadband*)

Set the accumulator’s deadband.

`SPI.setChipSelectActiveHigh` ()

Configure the chip select line to be active high.

`SPI.setChipSelectActiveLow` ()

Configure the chip select line to be active low.

`SPI.setClockActiveHigh` ()

Configure the clock output line to be active high. This is sometimes called clock polarity low or clock idle low.

`SPI.setClockActiveLow()`

Configure the clock output line to be active low. This is sometimes called clock polarity high or clock idle high.

`SPI.setClockRate(hz)`

Configure the rate of the generated clock signal. The default value is 500,000 Hz. The maximum value is 4,000,000 Hz.

**Parameters** `hz` – The clock rate in Hertz.

`SPI.setLSBFirst()`

Configure the order that bits are sent and received on the wire to be least significant bit first.

`SPI.setMSBFirst()`

Configure the order that bits are sent and received on the wire to be most significant bit first.

`SPI.setSampleDataOnFalling()`

Configure that the data is stable on the falling edge and the data changes on the rising edge.

`SPI.setSampleDataOnRising()`

Configure that the data is stable on the rising edge and the data changes on the falling edge.

`SPI.transaction(dataToSend)`

Perform a simultaneous read/write transaction with the device

**Parameters** `dataToSend` (*iterable of bytes*) – The data to be written out to the device

**Returns** data received from the device

Usage:

```
# send byte string
data = spi.transaction(b'stuff')

# send list of integers
data = spi.transaction([0x01, 0x02])
```

`SPI.write(dataToSend)`

Write data to the slave device. Blocks until there is space in the output FIFO.

If not running in output only mode, also saves the data received on the MISO input during the transfer into the receive FIFO.

**Parameters** `dataToSend` (*iterable of bytes*) – Data to send

**Returns** Number of bytes written

Usage:

```
# send byte string
writeCount = spi.write(b'stuff')

# send list of integers
writeCount = spi.write([0x01, 0x02])
```

## 1.4.60 Talon

`class wpilib.Talon(channel)`

Bases: `wpilib.SafePWM`

Cross the Road Electronics (CTRE) Talon and Talon SR Speed Controller via PWM

Constructor for a Talon (original or Talon SR)

**Parameters** `channel` (*int*) – The PWM channel that the Talon is attached to. 0-9 are on-board, 10-19 are on the MXP port

---

**Note:** The Talon uses the following bounds for PWM values. These values should work reasonably well for most controllers, but if users experience issues such as asymmetric behavior around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the Talon User Manual available from CTRE.

- 2.037ms = full “forward”
  - 1.539ms = the “high end” of the deadband range
  - 1.513ms = center of the deadband range (off)
  - 1.487ms = the “low end” of the deadband range
  - 0.989ms = full “reverse”
- 

**free** ()

**get** ()

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted** ()

Common interface for inverting the direction of a speed controller.

**Returns** The state of inversion (True is inverted)

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the PIDController.

**set** (*speed*, *syncGroup=0*)

Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting the direction of a speed controller.

**Parameters** `isInverted` – The state of inversion (True is inverted).

## 1.4.61 TalonSRX

**class** `wpilib.TalonSRX` (*channel*)

Bases: `wpilib.SafePWM`

Cross the Road Electronics (CTRE) Talon SRX Speed Controller via PWM

See also:

See *CANTalon* for CAN control of Talon SRX.

Constructor for a TalonSRX connected via PWM.

**Parameters** `channel` (*int*) – The PWM channel that the TalonSRX is attached to. 0-9 are on-board, 10-19 are on the MXP port.

---

**Note:** The TalonSRX uses the following bounds for PWM values. These values should work reasonably well for most controllers, but if users experience issues such as asymmetric behavior around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the TalonSRX User Manual available from CTRE.

- 2.004ms = full “forward”
  - 1.520ms = the “high end” of the deadband range
  - 1.500ms = center of the deadband range (off)
  - 1.480ms = the “low end” of the deadband range
  - 0.997ms = full “reverse”
- 

**free** ()

**get** ()

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted** ()

Common interface for the inverting direction of a speed controller.

**Returns** The state of inversion (True is inverted).

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the PIDController.

**set** (*speed*, *syncGroup=0*)

Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting direction of a speed controller.

**Parameters** `isInverted` – The state of inversion (True is inverted).

## 1.4.62 Timer

**class** `wpilib.Timer`

Bases: object

Provides time-related functionality for the robot

---

**Note:** Prefer to use this module for time functions, instead of the `time` module in the standard library. This will make it easier for your code to work properly in simulation.

---

**static delay** (*seconds*)

Pause the thread for a specified time. Pause the execution of the thread for a specified period of time given in seconds. Motors will continue to run at their last assigned values, and sensors will continue to update. Only the thread containing the wait will pause until the wait time is expired.

**Parameters seconds** (*float*) – Length of time to pause

**Warning:** If you're tempted to use this function for autonomous mode to time transitions between actions, don't do it!

Delaying the main robot thread for more than a few milliseconds is generally discouraged, and will cause problems and possibly leave the robot unresponsive.

**get** ()

Get the current time from the timer. If the clock is running it is derived from the current system clock the start time stored in the timer class. If the clock is not running, then return the time when it was last stopped.

**Returns** Current time value for this timer in seconds

**Return type** float

**static getFPGATimestamp** ()

Return the system clock time in seconds. Return the time from the FPGA hardware clock in seconds since the FPGA started.

**Returns** Robot running time in seconds.

**Return type** float

**static getMatchTime** ()

Return the approximate match time. The FMS does not currently send the official match time to the robots. This returns the time since the enable signal sent from the Driver Station. At the beginning of autonomous, the time is reset to 0.0 seconds. At the beginning of teleop, the time is reset to +15.0 seconds. If the robot is disabled, this returns 0.0 seconds.

**Warning:** This is not an official time (so it cannot be used to argue with referees).

**Returns** Match time in seconds since the beginning of autonomous

**Return type** float

**getMsClock** ()

**Returns** the system clock time in milliseconds.

**Return type** int

**hasPeriodPassed** (*period*)

Check if the period specified has passed and if it has, advance the start time by that period. This is useful to decide if it's time to do periodic work without drifting later by the time it took to get around to checking.

**Parameters period** – The period to check for (in seconds).

**Returns** If the period has passed.

**Return type** bool

**reset ()**

Reset the timer by setting the time to 0. Make the timer startTime the current time so new requests will be relative now.

**start ()**

Start the timer running. Just set the running flag to true indicating that all time requests should be relative to the system clock.

**stop ()**

Stop the timer. This computes the time as of now and clears the running flag, causing all subsequent time requests to be read from the accumulated time rather than looking at the system clock.

## 1.4.63 Ultrasonic

**class** `wpiplib.Ultrasonic` (*pingChannel, echoChannel, units=0*)

Bases: `wpiplib.SensorBase`

Ultrasonic rangefinder control

The Ultrasonic rangefinder measures absolute distance based on the round-trip time of a ping generated by the controller. These sensors use two transducers, a speaker and a microphone both tuned to the ultrasonic range. A common ultrasonic sensor, the Daventech SRF04 requires a short pulse to be generated on a digital channel. This causes the chirp to be emitted. A second line becomes high as the ping is transmitted and goes low when the echo is received. The time that the line is high determines the round trip distance (time of flight).

Create an instance of the Ultrasonic Sensor. This is designed to supchannel the Daventech SRF04 and Vex ultrasonic sensors.

### Parameters

- **pingChannel** – The digital output channel that sends the pulse to initiate the sensor sending the ping.
- **echoChannel** – The digital input channel that receives the echo. The length of time that the echo is high represents the round trip time of the ping, and the distance.
- **units** – The units returned in either kInches or kMillimeters

**class** `PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement = 0**

**kRate = 1**

**class** `Ultrasonic.Unit`

Bases: `object`

The units to return when PIDGet is called

**kInches = 0**

**kMillimeters = 1**

`Ultrasonic.automatedEnabled = False`

Automatic round robin mode

`Ultrasonic.free ()`

`Ultrasonic.getDistanceUnits()`

Get the current DistanceUnit that is used for the PIDSource interface.

**Returns** The type of DistanceUnit that is being used.

`Ultrasonic.getPIDSourceType()`

`Ultrasonic.getRangeInches()`

Get the range in inches from the ultrasonic sensor.

**Returns** Range in inches of the target returned from the ultrasonic sensor. If there is no valid value yet, i.e. at least one measurement hasn't completed, then return 0.

**Return type** float

`Ultrasonic.getRangeMM()`

Get the range in millimeters from the ultrasonic sensor.

**Returns** Range in millimeters of the target returned by the ultrasonic sensor. If there is no valid value yet, i.e. at least one measurement hasn't completed, then return 0.

**Return type** float

`Ultrasonic.instances = 0`

`static Ultrasonic.isAutomaticMode()`

`Ultrasonic.isEnabled()`

Is the ultrasonic enabled.

**Returns** True if the ultrasonic is enabled

`Ultrasonic.isRangeValid()`

Check if there is a valid range measurement. The ranges are accumulated in a counter that will increment on each edge of the echo (return) signal. If the count is not at least 2, then the range has not yet been measured, and is invalid.

**Returns** True if the range is valid

**Return type** bool

`Ultrasonic.kMaxUltrasonicTime = 0.1`

Max time (ms) between readings.

`Ultrasonic.kPingTime = 9.999999999999999e-06`

Time (sec) for the ping trigger pulse.

`Ultrasonic.kPriority = 90`

Priority that the ultrasonic round robin task runs.

`Ultrasonic.kSpeedOfSoundInchesPerSec = 13560.0`

`Ultrasonic.pidGet()`

Get the range in the current DistanceUnit (PIDSource interface).

**Returns** The range in DistanceUnit

**Return type** float

`Ultrasonic.ping()`

Single ping to ultrasonic sensor. Send out a single ping to the ultrasonic sensor. This only works if automatic (round robin) mode is disabled. A single ping is sent out, and the counter should count the semi-period when it comes in. The counter is reset to make the current value invalid.

`Ultrasonic.sensors = <_weakrefset.WeakSet object>`

ultrasonic sensor list



`Ultrasonic.setAutomaticMode` (*enabling*)

Turn Automatic mode on/off. When in Automatic mode, all sensors will fire in round robin, waiting a set time between each sensor.

**Parameters** `enabling` (*bool*) – Set to true if round robin scheduling should start for all the ultrasonic sensors. This scheduling method assures that the sensors are non-interfering because no two sensors fire at the same time. If another scheduling algorithm is preferred, it can be implemented by pinging the sensors manually and waiting for the results to come back.

`Ultrasonic.setDistanceUnits` (*units*)

Set the current DistanceUnit that should be used for the PIDSource interface.

**Parameters** `units` – The DistanceUnit that should be used.

`Ultrasonic.setEnabled` (*enable*)

Set if the ultrasonic is enabled.

**Parameters** `enable` (*bool*) – set to True to enable the ultrasonic

`Ultrasonic.setPIDSourceType` (*pidSource*)

Set which parameter you are using as a process control variable.

**Parameters** `pidSource` (*PIDSource.PIDSourceType*) – An enum to select the parameter.

`static Ultrasonic.ultrasonicChecker` ()

Background task that goes through the list of ultrasonic sensors and pings each one in turn. The counter is configured to read the timing of the returned echo pulse.

**Warning:** DANGER WILL ROBINSON, DANGER WILL ROBINSON: This code runs as a task and assumes that none of the ultrasonic sensors will change while it's running. If one does, then this will certainly break. Make sure to disable automatic mode before changing anything with the sensors!!

## 1.4.64 Utility

`class wpilib.Utility`

Bases: `object`

Contains global utility functions

`static getFPGARevision` ()

Return the FPGA Revision number. The format of the revision is 3 numbers. The 12 most significant bits are the Major Revision. the next 8 bits are the Minor Revision. The 12 least significant bits are the Build Number.

**Returns** FPGA Revision number.

**Return type** `int`

`static getFPGATime` ()

Read the microsecond timer from the FPGA.

**Returns** The current time in microseconds according to the FPGA.

**Return type** `int`

`static getFPGAVersion` ()

Return the FPGA Version number.

**Returns** FPGA Version number.

**Return type** int

**static** `getUserButton()`

Get the state of the “USER” button on the RoboRIO.

**Returns** True if the button is currently pressed down

**Return type** bool

## 1.4.65 Victor

**class** `wpilib.Victor(channel)`

Bases: `wpilib.SafePWM`

VEX Robotics Victor 888 Speed Controller via PWM

The Vex Robotics Victor 884 Speed Controller can also be used with this class but may need to be calibrated per the Victor 884 user manual.

---

**Note:** The Victor uses the following bounds for PWM values. These values were determined empirically and optimized for the Victor 888. These values should work reasonably well for Victor 884 controllers also but if users experience issues such as asymmetric behaviour around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the Victor 884 User Manual available from VEX Robotics: <http://content.vexrobotics.com/docs/ifi-v884-users-manual-9-25-06.pdf>

- 2.027ms = full “forward”
  - 1.525ms = the “high end” of the deadband range
  - 1.507ms = center of the deadband range (off)
  - 1.49ms = the “low end” of the deadband range
  - 1.026ms = full “reverse”
- 

Constructor.

**Parameters** `channel` (*int*) – The PWM channel that the Victor is attached to. 0-9 are on-board, 10-19 are on the MXP port

**free** ()

**get** ()

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted** ()

Common interface for the inverting direction of a speed controller.

**Returns** The state of inversion (True is inverted).

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** `output` (*float*) – Write out the PWM value as was found in the `PIDController`.

**set** (*speed*, *syncGroup=0*)  
Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting direction of a speed controller.

**Parameters** **isInverted** – The state of inversion (True is inverted).

## 1.4.66 VictorSP

**class** `wpiplib.VictorSP` (*channel*)

Bases: `wpiplib.SafePWM`

VEX Robotics Victor SP Speed Controller via PWM

Constructor.

**Parameters** **channel** (*int*) – The PWM channel that the VictorSP is attached to. 0-9 are on-board, 10-19 are on the MXP port.

---

**Note:** The Talon uses the following bounds for PWM values. These values should work reasonably well for most controllers, but if users experience issues such as asymmetric behavior around the deadband or inability to saturate the controller in either direction, calibration is recommended. The calibration procedure can be found in the VictorSP User Manual.

- 2.004ms = full “forward”
  - 1.520ms = the “high end” of the deadband range
  - 1.500ms = center of the deadband range (off)
  - 1.480ms = the “low end” of the deadband range
  - 0.997ms = full “reverse”
- 

**free** ()

**get** ()

Get the recently set value of the PWM.

**Returns** The most recently set value for the PWM between -1.0 and 1.0.

**Return type** float

**getInverted** ()

Common interface for the inverting direction of a speed controller.

**Returns** The state of inversion (True is inverted).

**pidWrite** (*output*)

Write out the PID value as seen in the PIDOutput base object.

**Parameters** **output** (*float*) – Write out the PWM value as was found in the PIDController.

**set** (*speed*, *syncGroup=0*)  
 Set the PWM value.

The PWM value is set using a range of -1.0 to 1.0, appropriately scaling the value for the FPGA.

**Parameters**

- **speed** (*float*) – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0, update immediately.

**setInverted** (*isInverted*)

Common interface for inverting direction of a speed controller.

**Parameters** **isInverted** – The state of inversion (True is inverted).

## 1.5 wpilib.buttons Package

Classes in this package are used to interface various types of buttons to a command-based robot.

If you are not using the Command framework, you can ignore these classes.

|  |  |
|--|--|
| <i>wpilib.buttons.Button</i>                 | This class provides an easy way to link commands to OI inputs. |
| <i>wpilib.buttons.InternalButton</i> ([...]) | This class is intended to be used within a program.            |
| <i>wpilib.buttons.JoystickButton</i> (...)   | Create a joystick button for triggering commands.              |
| <i>wpilib.buttons.NetworkButton</i> (...)    |  |
| <i>wpilib.buttons.Trigger</i>                | This class provides an easy way to link commands to inputs.    |

### 1.5.1 Button

**class** `wpilib.buttons.Button`

Bases: `wpilib.buttons.Trigger`

This class provides an easy way to link commands to OI inputs.

It is very easy to link a button to a command. For instance, you could link the trigger button of a joystick to a “score” command.

This class represents a subclass of `Trigger` that is specifically aimed at buttons on an operator interface as a common use case of the more generalized Trigger objects. This is a simple wrapper around Trigger with the method names renamed to fit the Button object use.

**cancelWhenPressed** (*command*)

Cancel the command when the button is pressed.

**Parameters** **command** –

**toggleWhenPressed** (*command*)

Toggles the command whenever the button is pressed (on then off then on).

**Parameters** **command** –

**whenPressed** (*command*)

Starts the given command whenever the button is newly pressed.

**Parameters** **command** – the command to start

**whenReleased** (*command*)

Starts the command when the button is released.

**Parameters** `command` – the command to start

**whileHeld** (*command*)

Constantly starts the given command while the button is held.

`Command.start()` will be called repeatedly while the button is held, and will be canceled when the button is released.

**Parameters** `command` – the command to start

## 1.5.2 InternalButton

**class** `wplib.buttons.InternalButton` (*inverted=False*)

Bases: `wplib.buttons.Button`

This class is intended to be used within a program. The programmer can manually set its value. Includes a setting for whether or not it should invert its value.

Creates an InternalButton which is inverted depending on the input.

**Parameters** `inverted` – If False, then this button is pressed when set to True, otherwise it is pressed when set to False.

**get** ()

**setInverted** (*inverted*)

**setPressed** (*pressed*)

## 1.5.3 JoystickButton

**class** `wplib.buttons.JoystickButton` (*joystick, buttonNumber*)

Bases: `wplib.buttons.Button`

Create a joystick button for triggering commands.

**Parameters**

- **joystick** – The GenericHID object that has the button (e.g. `Joystick`, `KinectStick`, etc)
- **buttonNumber** – The button number (see `GenericHID.getRawButton()`)

**get** ()

Gets the value of the joystick button.

**Returns** The value of the joystick button

## 1.5.4 NetworkButton

**class** `wplib.buttons.NetworkButton` (*table, field*)

Bases: `wplib.buttons.Button`

**get** ()

## 1.5.5 Trigger

**class** `wplib.buttons.Trigger`

Bases: `object`

This class provides an easy way to link commands to inputs.

It is very easy to link a button to a command. For instance, you could link the trigger button of a joystick to a “score” command.

It is encouraged that teams write a subclass of `Trigger` if they want to have something unusual (for instance, if they want to react to the user holding a button while the robot is reading a certain sensor input). For this, they only have to write the `get ()` method to get the full functionality of the `Trigger` class.

**cancelWhenActive** (*command*)

Cancels a command when the trigger becomes active.

**Parameters** `command` – the command to cancel

**get** ()

Returns whether or not the trigger is active

This method will be called repeatedly a command is linked to the `Trigger`.

**Returns** whether or not the trigger condition is active.

**grab** ()

Returns whether `get ()` returns `True` or the internal table for *SmartDashboard* use is pressed.

**toggleWhenActive** (*command*)

Toggles a command when the trigger becomes active.

**Parameters** `command` – the command to toggle

**whenActive** (*command*)

Starts the given command whenever the trigger just becomes active.

**Parameters** `command` – the command to start

**whenInactive** (*command*)

Starts the command when the trigger becomes inactive.

**Parameters** `command` – the command to start

**whileActive** (*command*)

Constantly starts the given command while the button is held.

`Command.start ()` will be called repeatedly while the trigger is active, and will be canceled when the trigger becomes inactive.

**Parameters** `command` – the command to start

## 1.6 wpilib.command Package

Objects in this package allow you to implement a robot using Command-based programming. Command based programming is a design pattern to help you organize your robot programs, by organizing your robot program into components based on *Command* and *Subsystem*

The python implementation of the Command framework closely follows the Java language implementation. RobotPy has several examples of command based robots available.

Each one of the objects in the Command framework has detailed documentation available. If you need more information, for examples, tutorials, and other detailed information on programming your robot using this pattern, we recommend that you consult the Java version of the [FRC Control System documentation](#)

|   |  |
|---|--|
| <code>wpiplib.command.Command([name, timeout])</code> | The Command class is at the very core of the entire command framework.                         |
| <code>wpiplib.command.CommandGroup([name])</code>     | A CommandGroup is a list of commands which are executed in sequence.                           |
| <code>wpiplib.command.PIDCommand(p, i, d)</code>      | This class defines a Command which interacts heavily with a PID loop.                          |
| <code>wpiplib.command.PIDSubsystem(p, i, d)</code>    | This class is designed to handle the case where there is a Subsystem which uses a PID loop.    |
| <code>wpiplib.command.PrintCommand(message)</code>    | A PrintCommand is a command which prints out a string when it is initialized.                  |
| <code>wpiplib.command.Scheduler()</code>              | The Scheduler is a singleton which holds the top-level running commands.                       |
| <code>wpiplib.command.StartCommand(...)</code>        | A StartCommand will call the start() method of another command when it is initialized.         |
| <code>wpiplib.command.Subsystem([name])</code>        | This class defines a major component of the robot.   |
| <code>wpiplib.command.WaitCommand(timeout)</code>     | A WaitCommand will wait for a certain amount of time before finishing.                         |
| <code>wpiplib.command.WaitForChildren(...)</code>     | This command will only finish if whatever <i>CommandGroup</i> it is in has no active children. |
| <code>wpiplib.command.WaitUntilCommand(time)</code>   | This will wait until the game clock reaches some value, then continue to the next command.     |

## 1.6.1 Command

**class** `wpiplib.command.Command` (*name=None, timeout=None*)

Bases: `wpiplib.Sendable`

The Command class is at the very core of the entire command framework. Every command can be started with a call to `start()`. Once a command is started it will call `initialize()`, and then will repeatedly call `execute()` until `isFinished()` returns True. Once it does, `end()` will be called.

However, if at any point while it is running `cancel()` is called, then the command will be stopped and `interrupted()` will be called.

If a command uses a *Subsystem*, then it should specify that it does so by calling the `requires()` method in its constructor. Note that a Command may have multiple requirements, and `requires()` should be called for each one.

If a command is running and a new command with shared requirements is started, then one of two things will happen. If the active command is interruptible, then `cancel()` will be called and the command will be removed to make way for the new one. If the active command is not interruptible, the other one will not even be started, and the active one will continue functioning.

**See also:**

`Subsystem`, `CommandGroup`

Creates a new command.

### Parameters

- **name** – The name for this command; if unspecified or None, The name of this command will be set to its class name.
- **timeout** – The time (in seconds) before this command “times out”. Default is no timeout. See `isTimedOut()`.

**cancel()**

This will cancel the current command.

This will cancel the current command eventually. It can be called multiple times. And it can be called when the command is not running. If the command is running though, then the command will be marked as canceled and eventually removed.

**Warning:** A command can not be canceled if it is a part of a *CommandGroup*, you must cancel the *CommandGroup* instead.

**doesRequire** (*system*)

Checks if the command requires the given *Subsystem*.

**Parameters** *system* – the system

**Returns** whether or not the subsystem is required, or False if given None.

**end** ()

Called when the command ended peacefully. This is where you may want to wrap up loose ends, like shutting off a motor that was being used in the command.

**execute** ()

The execute method is called repeatedly until this Command either finishes or is canceled.

**getGroup** ()

Returns the *CommandGroup* that this command is a part of. Will return None if this Command is not in a group.

**Returns** the *CommandGroup* that this command is a part of (or None if not in group)

**getName** ()

Returns the name of this command. If no name was specified in the constructor, then the default is the name of the class.

**Returns** the name of this command

**getRequirements** ()

Returns the requirements (as a set of Subsystems) of this command

**initialize** ()

The initialize method is called the first time this Command is run after being started.

**interrupted** ()

Called when the command ends because somebody called cancel() or another command shared the same requirements as this one, and booted it out.

This is where you may want to wrap up loose ends, like shutting off a motor that was being used in the command.

Generally, it is useful to simply call the end() method within this method.

**isCanceled** ()

Returns whether or not this has been canceled.

**Returns** whether or not this has been canceled

**isFinished** ()

Returns whether this command is finished. If it is, then the command will be removed and end() will be called.

It may be useful for a team to reference the isTimedOut() method for time-sensitive commands.

**Returns** whether this command is finished.

See *isTimedOut* ()

**isInterruptible** ()

Returns whether or not this command can be interrupted.

**Returns** whether or not this command can be interrupted



**isRunning()**

Returns whether or not the command is running. This may return true even if the command has just been canceled, as it may not have yet called *interrupted()*.

**Returns** whether or not the command is running

**isTimedOut()**

Returns whether or not the *timeSinceInitialized()* method returns a number which is greater than or equal to the timeout for the command. If there is no timeout, this will always return false.

**Returns** whether the time has expired

**lockChanges()**

Prevents further changes from being made

**removed()**

Called when the command has been removed. This will call *interrupted()* or *end()*.

**requires(subsystem)**

This method specifies that the given Subsystem is used by this command. This method is crucial to the functioning of the Command System in general.

Note that the recommended way to call this method is in the constructor.

**Parameters** **subsystem** – the *Subsystem* required

**run()**

The run method is used internally to actually run the commands.

**Returns** whether or not the command should stay within the Scheduler.

**setInterruptible(interruptible)**

Sets whether or not this command can be interrupted.

**Parameters** **interruptible** – whether or not this command can be interrupted

**setParent(parent)**

Sets the parent of this command. No actual change is made to the group.

**Parameters** **parent** – the parent

**setRunWhenDisabled(run)**

Sets whether or not this `{@link Command}` should run when the robot is disabled.

By default a command will not run when the robot is disabled, and will in fact be canceled.

**Parameters** **run** – whether or not this command should run when the robot is disabled

**setTimeout(seconds)**

Sets the timeout of this command.

**Parameters** **seconds** – the timeout (in seconds)

See *isTimedOut()*

**start()**

Starts up the command. Gets the command ready to start. Note that the command will eventually start, however it will not necessarily do so immediately, and may in fact be canceled before initialize is even called.

**startRunning()**

This is used internally to mark that the command has been started. The lifecycle of a command is:

- *startRunning()* is called.
- *run()* is called (multiple times potentially)

- `removed()` is called

It is very important that `startRunning()` and `removed()` be called in order or some assumptions of the code will be broken.

**startTiming()**

Called to indicate that the timer should start. This is called right before `initialize()` is, inside the `run()` method.

**timeSinceInitialized()**

Returns the time since this command was initialized (in seconds). This function will work even if there is no specified timeout.

**Returns** the time since this command was initialized (in seconds).

**willRunWhenDisabled()**

Returns whether or not this Command will run when the robot is disabled, or if it will cancel itself.

## 1.6.2 CommandGroup

**class** `wpiLib.command.CommandGroup` (*name=None*)

Bases: `wpiLib.command.Command`

A `CommandGroup` is a list of commands which are executed in sequence.

Commands in a `CommandGroup` are added using the `addSequential()` method and are called sequentially. `CommandGroups` are themselves `Commands` and can be given to other `CommandGroups`.

`CommandGroups` will carry all of the requirements of their subcommands. Additional requirements can be specified by calling `requires()` normally in the constructor.

`CommandGroups` can also execute commands in parallel, simply by adding them using `addParallel(...)`.

**See also:**

`Command`, `Subsystem`

Creates a new `CommandGroup` with the given name.

**Parameters** `name` – the name for this command group (optional). If `None`, the name of this command will be set to its class name.

**class** `Entry` (*command, state, timeout*)

Bases: `object`

**BRANCH\_CHILD = 2**

**BRANCH\_PEER = 1**

**IN\_SEQUENCE = 0**

**isTimedOut()**

`CommandGroup.addParallel` (*command, timeout=None*)

Adds a new child `Command` to the group (with an optional timeout). The `Command` will be started after all the previously added `Commands`.

Once the `Command` is started, it will run until it finishes, is interrupted, or the time expires (if a timeout is provided), whichever is sooner. Note that the given `Command` will have no knowledge that it is on a timer.

Instead of waiting for the child to finish, a `CommandGroup` will have it run at the same time as the subsequent `Commands`. The child will run until either it finishes, the timeout expires, a new child with conflicting requirements is started, or the main sequence runs a `Command` with conflicting requirements. In the latter two cases, the child will be canceled even if it says it can't be interrupted.

Note that any requirements the given Command has will be added to the group. For this reason, a Command's requirements can not be changed after being added to a group.

It is recommended that this method be called in the constructor.

#### Parameters

- **command** – The command to be added
- **timeout** – The timeout (in seconds) (optional)

`CommandGroup.addSequential (command, timeout=None)`

Adds a new Command to the group (with an optional timeout). The Command will be started after all the previously added Commands.

Once the Command is started, it will be run until it finishes or the time expires, whichever is sooner (if a timeout is provided). Note that the given Command will have no knowledge that it is on a timer.

Note that any requirements the given Command has will be added to the group. For this reason, a Command's requirements can not be changed after being added to a group.

It is recommended that this method be called in the constructor.

#### Parameters

- **command** – The Command to be added
- **timeout** – The timeout (in seconds) (optional)

`CommandGroup.cancelConflicts (command)`

`CommandGroup.end ()`

`CommandGroup.execute ()`

`CommandGroup.initialize ()`

`CommandGroup.interrupted ()`

`CommandGroup.isFinished ()`

Returns True if all the Commands in this group have been started and have finished.

Teams may override this method, although they should probably reference `super().isFinished()` if they do.

**Returns** whether this CommandGroup is finished

`CommandGroup.isInterruptible ()`

Returns whether or not this group is interruptible. A command group will be uninterruptible if `setInterruptible(False)` was called or if it is currently running an uninterruptible command or child.

**Returns** whether or not this CommandGroup is interruptible.

### 1.6.3 PIDCommand

**class** `wpiilib.command.PIDCommand (p, i, d, period=None, f=0.0, name=None)`

Bases: `wpiilib.command.Command`

This class defines a Command which interacts heavily with a PID loop.

It provides some convenience methods to run an internal PIDController. It will also start and stop said PIDController when the PIDCommand is first initialized and ended/interrupted.

Instantiates a PIDCommand that will use the given p, i and d values. It will use the class name as its name unless otherwise specified. It will also space the time between PID loop calculations to be equal to the given period.

#### Parameters

- **p** – the proportional value
- **i** – the integral value
- **d** – the derivative value
- **period** – the time (in seconds) between calculations (optional)
- **f** – the feed forward value
- **name** – the name (optional)

**getPIDController ()**

Returns the PIDController used by this PIDCommand. Use this if you would like to fine tune the pid loop.

Notice that calling `setSetpoint(...)` on the controller will not result in the setpoint being trimmed to be in the range defined by `setSetpointRange(...)`.

**Returns** the PIDController used by this PIDCommand

**getPosition ()**

Returns the current position

**Returns** the current position

**getSetpoint ()**

Returns the setpoint.

**Returns** the setpoint

**returnPIDInput ()**

Returns the input for the pid loop.

It returns the input for the pid loop, so if this command was based off of a gyro, then it should return the angle of the gyro

All subclasses of PIDCommand must override this method.

This method will be called in a different thread then the *Scheduler* thread.

**Returns** the value the pid loop should use as input

**setSetpoint (setpoint)**

Sets the setpoint to the given value. If `setRange ()` was called, then the given setpoint will be trimmed to fit within the range.

**Parameters** **setpoint** – the new setpoint

**setSetpointRelative (deltaSetpoint)**

Adds the given value to the setpoint. If `setRange ()` was used, then the bounds will still be honored by this method.

**Parameters** **deltaSetpoint** – the change in the setpoint

**usePIDOutput (output)**

Uses the value that the pid loop calculated. The calculated value is the “output” parameter. This method is a good time to set motor values, maybe something along the lines of *driveline.tankDrive(output, -output)*.

All subclasses of PIDCommand should override this method.

This method will be called in a different thread then the Scheduler thread.

**Parameters** **output** – the value the pid loop calculated

## 1.6.4 PIDSubsystem

**class** `wpiilib.command.PIDSubsystem` (*p*, *i*, *d*, *period=None*, *f=0.0*, *name=None*)

Bases: `wpiilib.command.Subsystem`

This class is designed to handle the case where there is a Subsystem which uses a single { @link PIDController } almost constantly (for instance, an elevator which attempts to stay at a constant height).

It provides some convenience methods to run an internal PIDController. It also allows access to the internal PIDController in order to give total control to the programmer.

Instantiates a PIDSubsystem that will use the given *p*, *i* and *d* values. It will use the class name as its name unless otherwise specified. It will also space the time between PID loop calculations to be equal to the given period.

### Parameters

- **p** – the proportional value
- **i** – the integral value
- **d** – the derivative value
- **period** – the time (in seconds) between calculations (optional)
- **f** – the feed forward value
- **name** – the name (optional)

**disable** ()

Disables the internal `PIDController`

**enable** ()

Enables the internal `PIDController`

**getPIDController** ()

Returns the PIDController used by this PIDSubsystem. Use this if you would like to fine tune the pid loop.

Notice that calling `setSetpoint ()` on the controller will not result in the setpoint being trimmed to be in the range defined by `setSetpointRange ()`.

**Returns** the `PIDController` used by this PIDSubsystem

**getPosition** ()

Returns the current position

**Returns** the current position

**getSetpoint** ()

Returns the setpoint.

**Returns** the setpoint

**onTarget** ()

Return True if the error is within the percentage of the total input range, determined by `setAbsoluteTolerance` or `setPercentTolerance`. This assumes that the maximum and minimum input were set using `setInput`.

**Returns** True if the error is less than the tolerance

**returnPIDInput** ()

Returns the input for the pid loop.

It returns the input for the pid loop, so if this command was based off of a gyro, then it should return the angle of the gyro

All subclasses of PIDSubsystem must override this method.

This method will be called in a different thread than the Scheduler thread.

**Returns** the value the pid loop should use as input

**setAbsoluteTolerance** (*t*)

Set the absolute error which is considered tolerable for use with OnTarget.

**Parameters** **t** – The absolute tolerance (same range as the PIDInput values)

**setInputRange** (*minimumInput, maximumInput*)

Sets the maximum and minimum values expected from the input.

**Parameters**

- **minimumInput** – the minimum value expected from the input
- **maximumInput** – the maximum value expected from the output

**setOutputRange** (*minimumOutput, maximumOutput*)

Sets the maximum and minimum values to write.

**Parameters**

- **minimumOutput** – the minimum value to write to the output
- **maximumOutput** – the maximum value to write to the output

**setPercentTolerance** (*p*)

Set the percentage error which is considered tolerable for use with OnTarget.

**Parameters** **p** – The percentage tolerance (value of 15.0 == 15 percent)

**setSetpoint** (*setpoint*)

Sets the setpoint to the given value. If `setRange()` was called, then the given setpoint will be trimmed to fit within the range.

**Parameters** **setpoint** – the new setpoint

**setSetpointRelative** (*deltaSetpoint*)

Adds the given value to the setpoint. If `setRange()` was used, then the bounds will still be honored by this method.

**Parameters** **deltaSetpoint** – the change in the setpoint

**usePIDOutput** (*output*)

Uses the value that the pid loop calculated. The calculated value is the “output” parameter. This method is a good time to set motor values, maybe something along the lines of `driveline.tankDrive(output, -output)`.

All subclasses of PIDSubsystem should override this method.

This method will be called in a different thread than the Scheduler thread.

**Parameters** **output** – the value the pid loop calculated

## 1.6.5 PrintCommand

**class** `wplib.command.PrintCommand` (*message*)

Bases: `wplib.command.Command`

A PrintCommand is a command which prints out a string when it is initialized, and then immediately finishes.

It is useful if you want a `CommandGroup` to print out a string when it reaches a certain point.

Instantiates a PrintCommand which will print the given message when it is run.

**Parameters** **message** – the message to print

`initialize()`

`isFinished()`

## 1.6.6 Scheduler

**class** `wpiplib.command.Scheduler`

Bases: `wpiplib.Sendable`

The Scheduler is a singleton which holds the top-level running commands. It is in charge of both calling the command's `run()` method and to make sure that there are no two commands with conflicting requirements running.

It is fine if teams wish to take control of the Scheduler themselves, all that needs to be done is to call `Scheduler.getInstance().run()` often to have Commands function correctly. However, this is already done for you if you use the `CommandBased Robot` template.

**See also:**

[\*Command\*](#)

Instantiates a Scheduler.

**add** (*command*)

Adds the command to the Scheduler. This will not add the *Command* immediately, but will instead wait for the proper time in the `run()` loop before doing so. The command returns immediately and does nothing if given null.

Adding a *Command* to the *Scheduler* involves the Scheduler removing any Command which has shared requirements.

**Parameters** `command` – the command to add

**addButton** (*button*)

Adds a button to the Scheduler. The Scheduler will poll the button during its `run()`.

**Parameters** `button` – the button to add

**disable** ()

Disable the command scheduler.

**enable** ()

Enable the command scheduler.

**static getInstance** ()

Returns the Scheduler, creating it if one does not exist.

**Returns** the Scheduler

**getName** ()

**getType** ()

**registerSubsystem** (*system*)

Registers a *Subsystem* to this Scheduler, so that the Scheduler might know if a default Command needs to be run. All *Subsystem* objects should call this.

**Parameters** `system` – the system

**remove** (*command*)

Removes the *Command* from the Scheduler.

**Parameters** `command` – the command to remove

**removeAll()**

Removes all commands

**run()**

Runs a single iteration of the loop. This method should be called often in order to have a functioning Command system. The loop has five stages:

- Poll the Buttons
- Execute/Remove the Commands
- Send values to SmartDashboard
- Add Commands
- Add Defaults

### 1.6.7 StartCommand

**class** `wpiplib.command.StartCommand` (*commandToStart*)

Bases: `wpiplib.command.Command`

A StartCommand will call the start() method of another command when it is initialized and will finish immediately.

Instantiates a StartCommand which will start the given command whenever its initialize() is called.

**Parameters** `commandToStart` – the *Command* to start

**initialize()**

**isFinished()**

### 1.6.8 Subsystem

**class** `wpiplib.command.Subsystem` (*name=None*)

Bases: `wpiplib.Sendable`

This class defines a major component of the robot.

A good example of a subsystem is the driveline, or a claw if the robot has one.

All motors should be a part of a subsystem. For instance, all the wheel motors should be a part of some kind of “Driveline” subsystem.

Subsystems are used within the command system as requirements for Command. Only one command which requires a subsystem can run at a time. Also, subsystems can have default commands which are started if there is no command running which requires this subsystem.

**See also:**

*Command*

Creates a subsystem.

**Parameters** `name` – the name of the subsystem; if None, it will be set to the name to the name of the class.

**confirmCommand()**

Call this to alert Subsystem that the current command is actually the command. Sometimes, the Subsystem is told that it has no command while the Scheduler is going through the loop, only to be soon after given a new one. This will avoid that situation.



**getCurrentCommand()**

Returns the command which currently claims this subsystem.

**Returns** the command which currently claims this subsystem

**getDefaultCommand()**

Returns the default command (or None if there is none).

**Returns** the default command

**getName()**

Returns the name of this subsystem, which is by default the class name.

**Returns** the name of this subsystem

**initDefaultCommand()**

Initialize the default command for a subsystem. By default subsystems have no default command, but if they do, the default command is set with this method. It is called on all Subsystems by CommandBase in the users program after all the Subsystems are created.

**setCurrentCommand(*command*)**

Sets the current command

**Parameters** **command** – the new current command

**setDefaultCommand(*command*)**

Sets the default command. If this is not called or is called with None, then there will be no default command for the subsystem.

**Parameters** **command** – the default command (or None if there should be none)

**Warning:** This should NOT be called in a constructor if the subsystem is a singleton.

## 1.6.9 WaitCommand

**class** `wplib.command.WaitCommand` (*timeout*, *name=None*)

Bases: `wplib.command.Command`

A WaitCommand will wait for a certain amount of time before finishing. It is useful if you want a `CommandGroup` to pause for a moment.

**See also:**

`CommandGroup`

Instantiates a WaitCommand with the given timeout.

**Parameters**

- **timeout** – the time the command takes to run
- **name** – the name of the command (optional)

**isFinished()**

## 1.6.10 WaitForChildren

**class** `wplib.command.WaitForChildren` (*name=None*, *timeout=None*)

Bases: `wplib.command.Command`

This command will only finish if whatever *CommandGroup* it is in has no active children. If it is not a part of a *CommandGroup*, then it will finish immediately. If it is itself an active child, then the *CommandGroup* will never end.

This class is useful for the situation where you want to allow anything running in parallel to finish, before continuing in the main *CommandGroup* sequence.

Creates a new command.

#### Parameters

- **name** – The name for this command; if unspecified or None, The name of this command will be set to its class name.
- **timeout** – The time (in seconds) before this command “times out”. Default is no timeout. See `isTimedOut()`.

`isFinished()`

### 1.6.11 WaitUntilCommand

`class wpilib.command.WaitUntilCommand(time)`

Bases: `wpilib.command.Command`

This will wait until the game clock reaches some value, then continue to the next command.

`isFinished()`

## 1.7 wpilib.interfaces Package

This package contains objects that can be used to determine the requirements of various interfaces used in WPILib.

Generally, the python version of WPILib does not require that you inherit from any of these interfaces, but instead will allow you to use custom objects as long as they have the same methods.

|  |  |
|--|--|
| <code>wpilib.interfaces.Accelerometer</code>   | Interface for 3-axis accelerometers  |
| <code>wpilib.interfaces.Controller</code>      | An interface for controllers.  |
| <code>wpilib.interfaces.CounterBase</code>     | Interface for counting the number of ticks on a digital input channel.                     |
| <code>wpilib.interfaces.GenericHID</code>      | GenericHID Interface   |
| <code>wpilib.interfaces.Gyro</code>            | Interface for yaw rate gyros   |
| <code>wpilib.interfaces.NamedSendable</code>   | The interface for sendable objects that gives the sendable a default name in the S         |
| <code>wpilib.interfaces.PIDInterface</code>    |  |
| <code>wpilib.interfaces.PIDOutput</code>       | This interface allows <code>PIDController</code> to write its results to its output.       |
| <code>wpilib.interfaces.PIDSource</code>       | This interface allows for <code>PIDController</code> to automatically read from this objec |
| <code>wpilib.interfaces.Potentiometer</code>   |  |
| <code>wpilib.interfaces.SpeedController</code> | Interface for speed controlling devices.   |

### 1.7.1 Accelerometer

`class wpilib.interfaces.Accelerometer`

Bases: `object`

Interface for 3-axis accelerometers

`class Range`

Bases: object

**k16G = 3**

**k2G = 0**

**k4G = 1**

**k8G = 2**

`Accelerometer.getX()`

Common interface for getting the x axis acceleration

**Returns** The acceleration along the x axis in g-forces

`Accelerometer.getY()`

Common interface for getting the y axis acceleration

**Returns** The acceleration along the y axis in g-forces

`Accelerometer.getZ()`

Common interface for getting the z axis acceleration

**Returns** The acceleration along the z axis in g-forces

`Accelerometer.setRange(range)`

Common interface for setting the measuring range of an accelerometer.

**Parameters** *range* – The maximum acceleration, positive or negative, that the accelerometer will measure. Not all accelerometers support all ranges.

## 1.7.2 Controller

**class** `wpiilib.interfaces.Controller`

Bases: object

An interface for controllers. Controllers run control loops, the most common are PID controllers and there variants, but this includes anything that is controlling an actuator in a separate thread.

**disable()**

Stops the control loop from running until explicitly re-enabled by calling `enable()`.

**enable()**

Allows the control loop to run.

## 1.7.3 CounterBase

**class** `wpiilib.interfaces.CounterBase`

Bases: object

Interface for counting the number of ticks on a digital input channel. Encoders, Gear tooth sensors, and counters should all subclass this so it can be used to build more advanced classes for control and driving.

All counters will immediately start counting - `reset()` them if you need them to be zeroed before use.

**class** `EncodingType`

Bases: object

The number of edges for the counterbase to increment or decrement on

**k1X = 0**

Count only the rising edge

**k2X = 1**

Count both the rising and falling edge

**k4X = 2**

Count rising and falling on both channels

`CounterBase.get()`

Get the count

**Returns** the count

`CounterBase.getDirection()`

Determine which direction the counter is going

**Returns** True for one direction, False for the other

`CounterBase.getPeriod()`

Get the time between the last two edges counted

**Returns** the time between the last two ticks in seconds

`CounterBase.getStopped()`

Determine if the counter is not moving

**Returns** True if the counter has not changed for the max period

`CounterBase.reset()`

Reset the count to zero

`CounterBase.setMaxPeriod(maxPeriod)`

Set the maximum time between edges to be considered stalled

**Parameters** `maxPeriod` – the maximum period in seconds

## 1.7.4 GenericHID

`class wpilib.interfaces.GenericHID`

Bases: object

GenericHID Interface

`class Hand`

Bases: object

Which hand the Human Interface Device is associated with.

**kLeft = 0**

Left hand

**kRight = 1**

Right hand

`GenericHID.getBumper(hand=None)`

Is the bumper pressed?

**Parameters** `hand` – which hand (default right)

**Returns** True if the bumper is pressed

`GenericHID.getPOV(pov=0)`

Get the state of a POV.

**Parameters** `pov` – which POV (default is 0)

**Returns** The angle of the POV in degrees, or -1 if the POV is not pressed.

`GenericHID.getRawAxis` (*which*)

Get the raw axis.

**Parameters** `which` – index of the axis

**Returns** the raw value of the selected axis

`GenericHID.getRawButton` (*button*)

Is the given button pressed?

**Parameters** `button` – which button number

**Returns** True if the button is pressed

`GenericHID.getThrottle` ()

Get the throttle.

**Returns** the throttle value

`GenericHID.getTop` (*hand=None*)

Is the top button pressed

**Parameters** `hand` – which hand (default right)

**Returns** True if the top button for the given hand is pressed

`GenericHID.getTrigger` (*hand=None*)

Is the trigger pressed

**Parameters** `hand` – which hand (default right)

**Returns** True if the trigger for the given hand is pressed

`GenericHID.getTwist` ()

Get the twist value.

**Returns** the twist value

`GenericHID.getX` (*hand=None*)

Get the x position of HID.

**Parameters** `hand` – which hand, left or right (default right)

**Returns** the x position

`GenericHID.getY` (*hand=None*)

Get the y position of the HID.

**Parameters** `hand` – which hand, left or right (default right)

**Returns** the y position

`GenericHID.getZ` (*hand=None*)

Get the z position of the HID.

**Parameters** `hand` – which hand, left or right (default right)

**Returns** the z position

## 1.7.5 Gyro

`class wpilib.interfaces.Gyro`

Bases: `object`

Interface for yaw rate gyros

**calibrate ()**

Calibrate the gyro by running for a number of samples and computing the center value. Then use the center value as the Accumulator center value for subsequent measurements.

---

**Note:** It's important to make sure that the robot is not moving while the centering calculations are in progress, this is typically done when the robot is first turned on while it's sitting at rest before the competition starts.

---

**free ()**

Free the resources used by the gyro

**getAngle ()**

Return the actual angle in degrees that the robot is currently facing.

The angle is based on the current accumulator value corrected by the oversampling rate, the gyro type and the A/D calibration values. The angle is continuous, that is it will continue from 360 to 361 degrees. This allows algorithms that wouldn't want to see a discontinuity in the gyro output as it sweeps past from 360 to 0 on the second time around.

**Returns** the current heading of the robot in degrees. This heading is based on integration of the returned rate from the gyro.

**getRate ()**

Return the rate of rotation of the gyro

The rate is based on the most recent reading of the gyro analog value

**Returns** the current rate in degrees per second

**reset ()**

Reset the gyro. Resets the gyro to a heading of zero. This can be used if there is significant drift in the gyro and it needs to be recalibrated after it has been running.

## 1.7.6 NamedSendable

**class** `wpiilib.interfaces.NamedSendable`

Bases: `wpiilib.Sendable`

The interface for sendable objects that gives the sendable a default name in the Smart Dashboard.

**getName ()**

**Returns** The name of the subtable of SmartDashboard that the `Sendable` object will use

## 1.7.7 PIDInterface

**class** `wpiilib.interfaces.PIDInterface`

Bases: `wpiilib.interfaces.Controller`

**disable ()**

**enable ()**

**getD ()**

**getError ()**

**getI ()**

```

getP ()
getSetpoint ()
isEnabled ()
reset ()
setPID (p, i, d)
setSetpoint (setpoint)

```

### 1.7.8 PIDOutput

**class** `wpiilib.interfaces.PIDOutput`

Bases: `object`

This interface allows `PIDController` to write its results to its output.

**pidWrite** (*output*)

Set the output to the value calculated by `PIDController`.

**Parameters** `output` – the value calculated by `PIDController`

### 1.7.9 PIDSource

**class** `wpiilib.interfaces.PIDSource`

Bases: `object`

This interface allows for `PIDController` to automatically read from this object.

**class** `PIDSourceType`

Bases: `object`

A description for the type of output value to provide to a `PIDController`

**kDisplacement** = 0

**kRate** = 1

**static** `PIDSource.from_obj_or_callable` (*objc*)

Utility method that gets a `PIDSource` object

**Parameters** `objc` – An object that implements the `PIDSource` interface, or a callable

**Returns** an object that implements the `PIDSource` interface

`PIDSource.getPIDSourceType` ()

**Get which parameter of the device you are using as a process control** variable.

**Returns** the currently selected `PID` source parameter

`PIDSource.pidGet` ()

Get the result to use in `PIDController`

**Returns** the result to use in `PIDController`

`PIDSource.setPIDSourceType` (*pidSource*)

Set which parameter of the device you are using as a process control variable.

**Parameters** `pidSource` (`PIDSourceType`) – An enum to select the parameter.

### 1.7.10 Potentiometer

```
class wpilib.interfaces.Potentiometer
    Bases: wpilib.interfaces.PIDSource

    get ()
```

### 1.7.11 SpeedController

```
class wpilib.interfaces.SpeedController
    Bases: wpilib.interfaces.PIDOutput
```

Interface for speed controlling devices.

```
disable ()
    Disable the speed controller.
```

```
get ()
    Common interface for getting the current set speed of a speed controller.
```

**Returns** The current set speed. Value is between -1.0 and 1.0.

```
getInverted ()
    Common interface for determining if a speed controller is in the inverted state or not.
```

**Returns** True if in inverted state

```
set (speed, syncGroup=0)
    Common interface for setting the speed of a speed controller.
```

**Parameters**

- **speed** – The speed to set. Value should be between -1.0 and 1.0.
- **syncGroup** – The update group to add this set() to, pending updateSyncGroup(). If 0 (or unspecified), update immediately.

```
setInverted (isInverted)
    Common interface for inverting direction of a speed controller.
```

**Parameters** **isInverted** – The state of inversion

```
stopMotor ()
    Stops motor movement. Motor can be moved again by calling set without having to re-enable the motor.
```

## 1.8 RobotPy Installer

---

**Note:** This is not the RobotPy installation guide, see [Getting Started](#) if you're looking for that!

---

Most FRC robots are not placed on networks that have access to the internet, particularly at competition arenas. The RobotPy installer is designed for this type of 'two-phase' operation – with individual steps for downloading and installing packages separately.

As of 2015, the RobotPy installer now supports downloading external packages from the python package repository (pypi) via pip, and installing those packages onto the robot. We cannot make any guarantees about the quality of external packages, so use them at your own risk.



**Note:** If your robot is on a network that has internet access, then you can manually install packages via `opkg` or `pip`. However, if you use the RobotPy installer to install packages, then you can easily reinstall them on your robot in the case you need to reimagine it.

If you choose to install packages manually via `pip`, keep in mind that when powered off, your RoboRIO does not keep track of the correct date, and as a result `pip` may fail with an SSL related error message. To set the date, you can either:

- Set the date via the web interface
- You can login to your roboRIO via SSH, and set the date via the `date` command:

```
date -s "2015-01-03 00:00:00"
```

Each of the commands supports various options, which you can read about by invoking the `--help` command.

### 1.8.1 install-robotpy

```
python3 installer.py install-robotpy
```

This will copy the appropriate RobotPy components to the robot, and install them. If the components are already installed on the robot, then they will be reinstalled.

### 1.8.2 download-robotpy

```
python3 installer.py download-robotpy
```

This will update the cached RobotPy packages to the newest versions available.

### 1.8.3 download

```
python3 installer.py download PACKAGE [PACKAGE ..]
```

Specify python package(s) to download, similar to what you would pass the `'pip install'` command. This command does not install files on the robot, and must be executed from a computer with internet access.

You can run this command multiple times, and files will not be removed from the download cache.

You can also use a *requirements.txt* file to specify which packages should be downloaded.

```
python3 installer.py download -r requirements.txt
```

### 1.8.4 install

```
python3 installer.py install PACKAGE [PACKAGE ..]
```

Copies python packages over to the roboRIO, and installs them. If the package already has been installed, it will be reinstalled.

You can also use a *requirements.txt* file to specify which packages should be downloaded.

```
python3 installer.py download -r requirements.txt
```

**Warning:** The ‘install’ command will only install packages that have been downloaded using the ‘download’ command, or packages that are on the robot’s pypi cache.

**Warning:** If your robot does not have a python3 interpreter installed, this command will fail. Run the *install-robotpy* command first.

## 1.9 Implementation Details

This page contains various design/implementation notes that are useful to people that are peering at the internals of WPILib/HAL. We will try to keep this document up to date...

### 1.9.1 Design Goals

The python implementation of WPILib/HAL is derived from the Java implementation of WPILib. In particular, we strive to keep the python implementation of WPILib as close to the spirit of the original WPILib java libraries as we can, only adding language-specific features where it makes sense.

Things that you won’t find in the original WPILib can be found in the `_impl` package.

If you have a suggestion for things to add to WPILib, we suggest adding it to the `robotpy_ext` package, which is a separate package for “high quality code of things that should be in WPILib, but aren’t”. This package is installed by the RobotPy installer by default.

### 1.9.2 HAL Loading

Currently, the HAL is split into two python packages:

- `hal` - Provided by the `robotpy-hal-base` package
- `hal_impl` - Provided by either `robotpy-hal-robotrio` or `robotpy-hal-sim`

You can only have a single `hal_impl` package installed in a particular python installation.

The `hal` package provides the definition of the functions and various types & required constants.

The `hal_impl` package provides the actual implementation of the HAL functions, or links them to a shared DLL via `ctypes`.

### 1.9.3 Adding options to robot.py

When `run()` is called, that function determines available commands that can be run, and parses command line arguments to pass to the commands. Examples of commands include:

- Running the robot code
- Running the robot code, connected to a simulator
- Running unit tests on the robot code
- And lots more!

python `setuptools` has a feature that allows you to extend the commands available to `robot.py` without needing to modify WPILib’s code. To add your own command, do the following:

- Define a setuptools entrypoint in your package's setup.py (see below)
- The entrypoint name is the command to add
- **The entrypoint must point at an object that has the following properties:**
  - Must have a docstring (shown when `-help` is given)
  - Constructor must take a single argument (it is an argparse parser which options can be added to)
  - Must have a 'run' function which takes two arguments: options, and robot\_class. It must also take arbitrary keyword arguments via the `**kwargs` mechanism. If it receives arguments that it does not recognize, the entry point must ignore any such options.

If your command's run function is called, it is your command's responsibility to execute the robot code (if that is desired). This sample command demonstrates how to do this:

```
class SampleCommand:
    '''Help text shown to user'''

    def __init__(self, parser):
        pass

    def run(self, options, robot_class, **static_options):
        # runs the robot code main loop
        robot_class.main(robot_class)
```

To register your command as a robotpy extension, you must add the following to your setup.py setup() invocation:

```
from setuptools import setup

setup(
    ...
    entry_points={'robot_py': ['name_of_command = package.module:CommandClassName']},
    ...
)
```

## 1.10 Support

The RobotPy project was started in 2010, and since then the community surrounding RobotPy has continued to grow! If you have questions about how to do something with RobotPy, you can ask questions in the following locations:

- [RobotPy mailing list](#)
- [ChiefDelphi Python Forums](#)

We have found that most problems users have are actually questions generic to WPILib-based languages like C++/Java, so searching around the ChiefDelphi forums could be useful if you don't have a python-specific question.

During the FRC build season, you can probably expect answers to your questions within a day or two if you send messages to the mailing list. As community members are also members of FRC teams, you can expect that the closer we get to the end of the build season, the harder it will be for community members to respond to your questions!

### 1.10.1 Reporting Bugs

If you run into a problem with RobotPy that you think is a bug, or perhaps there is something wrong with the documentation or just too difficult to do, please feel free to file bug reports on the [github issue tracker](#). Someone should respond within a day or two, especially during the FIRST build season.

### 1.10.2 Contributing new fixes or features

RobotPy is intended to be a project that all members of the FIRST community can **quickly** and **easily** contribute to. If you find a bug, or have an idea that you think others can use:

1. Fork [this git repository](#) to your github account
2. Create your feature branch (*git checkout -b my-new-feature*)
3. Commit your changes (*git commit -am 'Add some feature'*)
4. Push to the branch (*git push -u origin my-new-feature*)
5. Create new Pull Request on github

Github has a lot of documentation about [forking repositories](#) and [pull requests](#), so be sure to check out those resources.

### 1.10.3 IRC

During the FRC Build Season, some RobotPy developers may be able to be reached on **#robotpy** channel on [Freenode](#).

---

**Note:** the channel is not very active, but if you stick around for a day or two someone will probably answer your question – think in terms of email response time

The channel tends to be most active between 11pm and 1am EST.

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## Indices and tables

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