Welcome to the API reference documentation for Adafruit CircuitPython. This contains low-level API reference docs which may link out to separate “getting started” guides. Adafruit has many excellent tutorials available through the Adafruit Learning System.
CircuitPython is a beginner friendly, open source version of Python for tiny, inexpensive computers called microcontrollers. Microcontrollers are the brains of many electronics including a wide variety of development boards used to build hobby projects and prototypes. CircuitPython in electronics is one of the best ways to learn to code because it connects code to reality. Simply install CircuitPython on a supported USB board usually via drag and drop and then edit a code.py file on the CIRCUITPY drive. The code will automatically reload. No software installs are needed besides a text editor (we recommend Mu for beginners.)

Starting with CircuitPython 7.0.0, some boards may only be connectable over Bluetooth Low Energy (BLE). Those boards provide serial and file access over BLE instead of USB using open protocols. (Some boards may use both USB and BLE.) BLE access can be done from a variety of apps including code.circuitpython.org.

CircuitPython features unified Python core APIs and a growing list of 300+ device libraries and drivers that work with it. These libraries also work on single board computers with regular Python via the Adafruit Blinka Library.

CircuitPython is based on MicroPython. See below for differences. Most, but not all, CircuitPython development is sponsored by Adafruit and is available on their educational development boards. Please support both MicroPython and Adafruit.

1.1 Get CircuitPython

Official binaries for all supported boards are available through circuitpython.org/downloads. The site includes stable, unstable and continuous builds. Full release notes are available through GitHub releases as well.
1.2 Documentation

Guides and videos are available through the Adafruit Learning System under the CircuitPython category. An API reference is also available on Read the Docs. A collection of awesome resources can be found at Awesome CircuitPython.

Specifically useful documentation when starting out:
- Welcome to CircuitPython
- CircuitPython Essentials
- Example Code

1.3 Code Search

GitHub doesn’t currently support code search on forks. Therefore, CircuitPython doesn’t have code search through GitHub because it is a fork of MicroPython. Luckily, SourceGraph has free code search for public repos like CircuitPython. So, visit sourcegraph.com/github.com/adafruit/circuitpython to search the CircuitPython codebase online.

1.4 Contributing

See CONTRIBUTING.md for full guidelines but please be aware that by contributing to this project you are agreeing to the Code of Conduct. Contributors who follow the Code of Conduct are welcome to submit pull requests and they will be promptly reviewed by project admins. Please join the Discord too.

1.5 Branding

While we are happy to see CircuitPython forked and modified, we’d appreciate it if forked releases not use the name “CircuitPython” or the Blinka logo. “CircuitPython” means something special to us and those who learn about it. As a result, we’d like to make sure products referring to it meet a common set of requirements.

If you’d like to use the term “CircuitPython” and Blinka for your product here is what we ask:

- Your product is supported by the primary “adafruit/circuitpython” repo. This way we can update any custom code as we update the CircuitPython internals.
- Your product is listed on circuitpython.org (source here). This is to ensure that a user of your product can always download the latest version of CircuitPython from the standard place.
- Your product supports at least one standard “Workflow” for serial and file access:
  - With a user accessible USB plug which appears as a CIRCUITPY drive when plugged in.
  - With file and serial access over Bluetooth Low Energy using the BLE Workflow.
  - With file access over WiFi using the WiFi Workflow with serial access over USB and/or WebSocket.
- Boards that do not support the USB Workflow should be clearly marked.

If you choose not to meet these requirements, then we ask you call your version of CircuitPython something else (for example, SuperDuperPython) and not use the Blinka logo. You can say it is “CircuitPython-compatible” if most CircuitPython drivers will work with it.
## 1.6 Differences from MicroPython

CircuitPython:

- Supports native USB on most boards and BLE otherwise, allowing file editing without special tools.
- Floats (aka decimals) are enabled for all builds.
- Error messages are translated into 10+ languages.
- Concurrency within Python is not well supported. Interrupts and threading are disabled. async/await keywords are available on some boards for cooperative multitasking. Some concurrency is achieved with native modules for tasks that require it such as audio file playback.

### 1.6.1 Behavior

- The order that files are run and the state that is shared between them. CircuitPython’s goal is to clarify the role of each file and make each file independent from each other.
  - `boot.py` runs only once on start up before workflows are initialized. This lays the groundwork for configuring USB at startup rather than it being fixed. Since serial is not available, output is written to `boot_out.txt`.
  - `code.py` (or `main.py`) is run after every reload until it finishes or is interrupted. After it is done running, the vm and hardware is reinitialized. **This means you cannot read state from code.py in the REPL anymore, as the REPL is a fresh vm.** CircuitPython’s goal for this change includes reducing confusion about pins and memory being used.
  - After the main code is finished the REPL can be entered by pressing any key.
  - Autoreload state will be maintained across reload.

- Adds a safe mode that does not run user code after a hard crash or brown out. This makes it possible to fix code that causes nasty crashes by making it available through mass storage after the crash. A reset (the button) is needed after it’s fixed to get back into normal mode.

- RGB status LED indicating CircuitPython state. - One green flash - code completed without error. - Two red flashes - code ended due to an exception. - Three yellow flashes - safe mode. May be due to CircuitPython internal error.

- Re-runs `code.py` or other main file after file system writes by a workflow. (Disable with `supervisor.disable_autoreload()`)

- Autoreload is disabled while the REPL is active.

- Main is one of these: `code.txt`, `code.py`, `main.py`, `main.txt`

- Boot is one of these: `boot.py`, `boot.txt`
1.6.2 API

- Unified hardware APIs. Documented on ReadTheDocs.
- API docs are Python stubs within the C files in shared-bindings.
- No machine API.

1.6.3 Modules

- No module aliasing. (uos and utime are not available as os and time respectively.) Instead os, time, and random are CPython compatible.
- New storage module which manages file system mounts. (Functionality from uos in MicroPython.)
- Modules with a CPython counterpart, such as time, os and random, are strict subsets of their CPython version. Therefore, code from CircuitPython is runnable on CPython but not necessarily the reverse.
- tick count is available as time.monotonic()

1.7 Project Structure

Here is an overview of the top-level source code directories.

1.7.1 Core

The core code of MicroPython is shared amongst ports including CircuitPython:
- docs High level user documentation in Sphinx reStructuredText format.
- drivers External device drivers written in Python.
- examples A few example Python scripts.
- extmod Shared C code used in multiple ports’ modules.
- lib Shared core C code including externally developed libraries such as FATFS.
- logo The CircuitPython logo.
- mpy-cross A cross compiler that converts Python files to byte code prior to being run in MicroPython. Useful for reducing library size.
- py Core Python implementation, including compiler, runtime, and core library.
- shared-bindings Shared definition of Python modules, their docs and backing C APIs. Ports must implement the C API to support the corresponding module.
- shared-module Shared implementation of Python modules that may be based on common-hal.
- tests Test framework and test scripts.
- tools Various tools, including the pyboard.py module.
1.7.2 Ports

Ports include the code unique to a microcontroller line.

<table>
<thead>
<tr>
<th>Supported</th>
<th>Support status</th>
</tr>
</thead>
<tbody>
<tr>
<td>atmel-samd</td>
<td>SAMD21 stable</td>
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<tr>
<td>cxd56</td>
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<td>espressif</td>
<td>ESP32 beta</td>
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<td>litex</td>
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<td>mimxrt10xx</td>
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<td>nrf</td>
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<td>stm</td>
<td>F4 stable</td>
</tr>
<tr>
<td>unix</td>
<td>alpha</td>
</tr>
</tbody>
</table>

- **stable** Highly unlikely to have bugs or missing functionality.
- **beta** Being actively improved but may be missing functionality and have bugs.
- **alpha** Will have bugs and missing functionality.

1.7.3 Boards

- Each port has a boards directory containing boards which belong to a specific microcontroller line.
- A list of native modules supported by a particular board can be found here.

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1.8 Full Table of Contents

1.8.1 Core Modules

These core modules are intended on being consistent across ports and boards. A module may not exist on a port/board if no underlying hardware support is present or if flash space is limited. For example, a microcontroller without analog features will not have `analogio`. See the `Module Support Matrix - Which Modules Are Available on Which Boards` page for a list of modules supported on each board.

**Module Support Matrix - Which Modules Are Available on Which Boards**

The following table lists the available built-in modules for each CircuitPython capable board, as well as each `frozen module` included on it.

You can filter this list by typing one or more module names or partial names into the search box. Only those boards that provide those modules will be listed. To exclude boards that provide a module, type a “-” in front of the module name. You can also type a regular expression as a filter.
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<thead>
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<th>Board</th>
<th>Modules Available</th>
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<td>8086 Commander</td>
<td>Frozen Modules: adafruit_hid, adafruit_sdcard</td>
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<th>Board</th>
<th>Modules Available</th>
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<td>rgbmatrix, rotaryio, rtc, scardio, select, sharpdisplay, socketpool, ssl, storage,</td>
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<td>struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab,</td>
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<td>usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>i2ctarget, ipaddress, json, keypad, math, mdns, microcontroller, msgpack,</td>
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<td>neopixel_write, nvm, onewireio, os, ps2io, pulseio, pmnio, rainbowio, random, re,</td>
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Frozen Modules: adafruit_crickit, adafruit_motor, adafruit_seesaw, neopixel

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<td><strong>Frozen Modules:</strong> adafruit_rfm69</td>
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<th>Board</th>
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<tr>
<td>Adafruit Feather</td>
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<td>RP2040</td>
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<td>paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharppixel, storage, struct, supervisor,</td>
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<td>Scorpio</td>
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<td>Adafruit Feather</td>
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<td>STM32F405 Express</td>
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<td><strong>Frozen Modules:</strong> adafruit_display_text, adafruit_fakerequests, adafruit_portalbase, adafruit_requests, neopixel</td>
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<td>Gemma M0</td>
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<td>Gemma M0 PyCon 2018</td>
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1.8. Full Table of Contents
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<th>Board</th>
<th>Modules Available</th>
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<td>Driver</td>
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<td>adafruit_display_text, adafruit_fakerequests, adafruit_lis3dh, adafruit_portalbase, adafruit_requests, neopixel</td>
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<th>Board</th>
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<td>neopixel_write, nvm, onewireio, os, ps2io, pulseio, pwmio, rainbowio, random, re,</td>
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<td>usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td><strong>Frozen Modules:</strong></td>
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<td>Trinkey</td>
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<td>Adafruit Rotary</td>
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<td>Trinkey M0</td>
<td><strong>Frozen Modules</strong>: adafruit_hid, neopixel</td>
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<td>Adafruit Slide</td>
<td>adafruit_pixelbuf, analogio, array, board, builtins, collections, digitalio, math, microcontroller, neopixel_write, nvm, os, rainbowio, random, storage, struct, supervisor, sys, time, touchio, usbcdc, usbhid, usbmidi</td>
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<td>Trinkey M0</td>
<td><strong>Frozen Modules</strong>: adafruit_hid, adafruit_simplemath, neopixel</td>
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<td>dotenv, errno, floppio, fontio, framebufferio, frequencyio, getpass, i2c_target,</td>
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<td>json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os,</td>
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<td>watchdog, zlib</td>
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<td>Adafruit Trinket M0</td>
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<td>rtc, storage, struct, supervisor, sys, time, touchio, usb_cdc, usb_hid, usb_mid</td>
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<td>AITHinker ESP32-C3S_Kit</td>
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<td>ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab, vectorio, watchdog, wifi, zlib</td>
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<td>AITHinker ESP32-C3S_Kit_2M</td>
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<td>Alori-umTech Evo M51</td>
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<td>displayio, dotenv, errno, floppio, fontio, framebufferio, frequencyio, getpass, i2c_target, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallel_display, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab, usb_cdc, usb_hid, usb_mid, vectorio, watchdog, zlib</td>
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<td>ARAM-CON Badge 2019</td>
<td><code>_asyncio</code>, <code>_bleio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>audiomp3</code>, <code>audiopwmio</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtins</code>, <code>busio</code>, <code>collections</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>errno</code>, <code>fontio</code>, <code> framebufferio</code>, <code>getpass</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>parallelidisplay</code>, <code>pulseio</code>, <code>pwmio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgbmatrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharppdisplay</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>zlib</code></td>
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<td>Arduino Nano 33 BLE</td>
<td><code>_asyncio</code>, <code>_bleio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>audiomp3</code>, <code>audiopwmio</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtins</code>, <code>busio</code>, <code>collections</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>errno</code>, <code>fontio</code>, <code> framebufferio</code>, <code>getpass</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>parallelidisplay</code>, <code>pulseio</code>, <code>pwmio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgbmatrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharppdisplay</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>zlib</code></td>
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<td>Atelier-DuMaker nRF52840 Breakout</td>
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<td>AT-MegaZero ESP32-S2</td>
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<td>__asyncio, __bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, audiomp3, audiopwmio, binascii, bitbangio, bitmapools, board, builtins, busio, canio, collections, countio, digitalio, displayio, dotenv, ermm, fontio, framebufferio, getpass, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>BBQ20KBD</td>
<td><code>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogbufio, analogio, array, atexit, audiobusio, audiocore, audiomixer, audiomp3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, error, floppyio, fontio, framebufferio, getpass, i2c_target, imagecapture, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallel_display, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zlib</code></td>
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<td>Bee-Motion-S3</td>
<td><code>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, error, fontio, framebufferio, frequencyio, getpass, hashlib, i2c_target, ipaddress, json, keypad, math, mDNS, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ublab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</code></td>
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<td><strong>Frozen Modules:</strong> neopixel</td>
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<td>BLE-SS dev board Multi Sensor</td>
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<td>BlueMicro833</td>
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<td>BPI-Leaf-S3</td>
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<td>Challenger RP2040 LTE</td>
<td>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogbufio, analogio, array, atexit, audiobsio, audiocore, audiomixer, audiopm3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, errno, flopppyio, fontio, framebufferio, getpass, i2ctarget, imagecapture, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zlib</td>
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<td>Challenger RP2040 SubGHz</td>
<td>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogbufio, analogio, array, atexit, audiobsio, audiocore, audiomixer, audiopm3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, errno, flopppyio, fontio, framebufferio, getpass, i2ctarget, imagecapture, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zlib</td>
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<td>Challenger RP2040 WiFi</td>
<td>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogbufio, analogio, array, atexit, audiobsio, audiocore, audiomixer, audiopm3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, errno, flopppyio, fontio, framebufferio, getpass, i2ctarget, imagecapture, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zlib</td>
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Frozen Modules: adafruit_rf9x

Frozen Modules: adafruit_rf69

Frozen Modules: adafruit_rfm69

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<td>Circuit Playground Express</td>
<td>adafruit_bus_device, adafruit_pixelbuf, analogio, array, audiobusio, audiocore, audioio, bitbangio, board, builtins, busio, collections, countio, digitalio, dotenv, errno, fontio, math, microcontroller, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, rainbowio, random, rotaryio, rtc, storage, struct, supervisor, sys, time, touchio, usb_cdc, usb_hid, usb_midi</td>
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<td>Digi-Key PyCon 2019</td>
<td><strong>Frozen Modules:</strong> adafruit_circuitplayground, adafruit_hid, adafruit_lis3dh, adafruit_thermistor, neopixel</td>
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<td>Cytron Maker</td>
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Frozen Modules: `neopixel`
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| Feather ESP32S2 without PSRAM | `_asyncio`, `adafruit_bus_device`, `adafruit_pixelbuf`, `aesio`, `alarm`, `analogio`, `array`, `atexit`, `audiobusio`, `audiocore`, `audiomixer`, `binascii`, `bitbangio`, `bitmapools`, `board`, `builts`, `busio`, `canio`, `collections`, `cproc`, `countio`, `digitalio`, `displayio`, `dotenv`, `dualbank`, `errno`, `fontio`, `framebufferio`, `frequencyio`, `getpass`, `hashlib`, `i2c_target`, `ipaddress`, `json`, `keypad`, `math`, `mdns`, `microcontroller`, `msgpack`, `neopixel_write`, `nvm`, `onewireio`, `os`, `paralleldisplay`, `ps2io`, `pulsio`, `pwmio`, `rainbowio`, `random`, `re`, `rgbmatrix`, `rotaryio`, `rtc`, `sdcardio`, `select`, `sharppdispay`, `socketpool`, `ssl`, `storage`, `struct`, `supervisor`, `synthio`, `sys`, `terminalio`, `time`, `touchio`, `traceback`, `ulab`, `usb_cdc`, `usb_hid`, `usb_midi`, `vectorio`, `watchdog`, `wifi`, `zlib`  
**Frozen Modules:** `adafruit_register`, `adafruit_requests`, `neopixel` |
| Feather MIMXRT1062 | `_asyncio`, `_bleio`, `adafruit_bus_device`, `adafruit_pixelbuf`, `aesio`, `analogio`, `array`, `atexit`, `binascii`, `bitbangio`, `bitmapools`, `board`, `builts`, `busio`, `collections`, `digitalio`, `displayio`, `dotenv`, `errno`, `fontio`, `framebufferio`, `getpass`, `json`, `keypad`, `math`, `microcontroller`, `msgpack`, `neopixel_write`, `onewireio`, `os`, `pwmio`, `rainbowio`, `random`, `re`, `rtc`, `sdcardio`, `select`, `sharppdispay`, `storage`, `struct`, `supervisor`, `sys`, `terminalio`, `time`, `touchio`, `traceback`, `ulab`, `usb_cdc`, `usb_hid`, `usb_midi`, `vectorio`, `zlib`  
**Frozen Modules:** `adafruit_spi32`, `adafruit_requests` |
| Feather MIMXRT1062 | `_asyncio`, `_bleio`, `adafruit_bus_device`, `adafruit_pixelbuf`, `aesio`, `analogio`, `array`, `atexit`, `binascii`, `bitbangio`, `bitmapools`, `board`, `builts`, `busio`, `collections`, `digitalio`, `displayio`, `dotenv`, `errno`, `fontio`, `framebufferio`, `getpass`, `gifio`, `hashlib`, `i2c_target`, `ipaddress`, `json`, `keypad`, `math`, `mdns`, `microcontroller`, `msgpack`, `neopixel_write`, `nvm`, `onewireio`, `os`, `paralleldisplay`, `ps2io`, `pulsio`, `pwmio`, `qrio`, `rainbowio`, `random`, `re`, `rgbmatrix`, `rotaryio`, `rtc`, `sdcardio`, `select`, `sharppdispay`, `socketpool`, `ssl`, `storage`, `struct`, `supervisor`, `synthio`, `sys`, `terminalio`, `time`, `touchio`, `traceback`, `ulab`, `usb_cdc`, `usb_hid`, `usb_midi`, `vectorio`, `watchdog`, `wifi`, `zlib` |

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<td>FeatherS2 PreRelease</td>
<td><code>asyncio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtins</code>, <code>busio</code>, <code>canio</code>, <code>collections</code>, <code>cproc</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>dualbank</code>, <code>errno</code>, <code>fontio</code>, <code>framebufferio</code>, <code>frequencyio</code>, <code>getpass</code>, <code>gifio</code>, <code>hashlib</code>, <code>i2c_target</code>, <code>ipaddress</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>mdns</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>parallel_display</code>, <code>ps2io</code>, <code>pulsio</code>, <code>pmvio</code>, <code>qrio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgb_matrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharpdisplay</code>, <code>socketpool</code>, <code>ssl</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>wifi</code>, <code>zlib</code></td>
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<td>Frozen Modules: <code>neopixel</code></td>
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<td>FeatherS3</td>
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<td>Fig Pi</td>
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<td>Fluff M0</td>
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<td>Fomu</td>
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<td>Franzininho WIFI w/Wrooom</td>
<td>._asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, frequencyio, getpass, hashlib, i2c_target, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallelledisplay, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchscreen, traceback, ubab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>Franzininho WIFI w/Wrooom</td>
<td>._asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, frequencyio, getpass, gifio, hashlib, i2c_target, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallelledisplay, ps2io, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchscreen, traceback, ubab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>Gravitech Cucumber M</td>
<td>._asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, frequencyio, getpass, hashlib, i2c_target, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallelledisplay, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchscreen, traceback, ubab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>Gravitech Cucumber MS</td>
<td>._asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, frequencyio, getpass, hashlib, i2c_target, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, parallelledisplay, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchscreen, traceback, ubab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<tr>
<td>Gravitech Cucumber RS</td>
<td><code>_asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, freqencyio, getpass, gifio, hashlib, i2cdevice, ipaddress, json, keypad, math, mDNS, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, ps2io, pulseio, pwmio, qrio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ubin, web_dcd, web_hid, web_midi, vectorio, watchdog, wifi, zlib</code></td>
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<tr>
<td>Hacked Feather M0 Express with 8Mbyte SPI flash</td>
<td><code>adafruit_pixelbuf, analogio, array, audiobusio, audiocore, audioio, board, builtins, busio, collections, digitalio, displayio, dotenv, errno, fontio, math, microcontroller, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, rainbowio, random, rotaryio, rtc, storage, struct, supervisor, sys, terminalio, time, touchio, web_dcd, web_hid, web_midi</code></td>
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<td>HalloWing M0 Express</td>
<td><code>adafruit_pixelbuf, analogio, array, audiocore, audioio, board, builtins, busio, collections, digitalio, displayio, dotenv, errno, fontio, math, microcontroller, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, rainbowio, random, rotaryio, rtc, storage, struct, supervisor, sys, terminalio, time, touchio, web_dcd, web_hid, web_midi</code> <strong>Frozen Modules:</strong> adafruit_lis3dh, neopixel</td>
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<tr>
<td>Hardkernel Odroid Go</td>
<td><code>_asyncio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, binascii, bitbangio, bitmaptools, board, builtins, busio, canio, collections, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, freqencyio, getpass, gifio, hashlib, i2cdevice, ipaddress, json, keypad, math, mDNS, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ubin, vectorio, watchdog, wifi, zlib</code></td>
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<td>HexKyS2</td>
<td><code>_asyncio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtsins</code>, <code>busio</code>, <code>canio</code>, <code>collections</code>, <code>cproc</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>dualbank</code>, <code>errno</code>, <code>fontio</code>, <code>framebufferio</code>, <code>frequencyio</code>, <code>getpass</code>, <code>gifio</code>, <code>hashlib</code>, <code>i2ctarget</code>, <code>ipaddress</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>mdns</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>paralleldisplay</code>, <code>ps2io</code>, <code>pulseeio</code>, <code>pwmio</code>, <code>qrio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgbmatrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharpendisplay</code>, <code>socketpool</code>, <code>ssl</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>wifi</code>, <code>zlib</code>&lt;br&gt;<strong>Frozen Modules:</strong> <code>neopixel</code></td>
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<td>HiiBot BlueFi</td>
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<td>HMI DevKit-1.1</td>
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<td>Iki-gaiSense Vita nRF52840</td>
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<td>iLabs Challenger 840</td>
<td><code>_asyncio</code>, <code>_bleio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>audiomp3</code>, <code>audiopwmio</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtsins</code>, <code>busio</code>, <code>collections</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>dualbank</code>, <code>errno</code>, <code>fontio</code>, <code>framebufferio</code>, <code>getpass</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>paralleldisplay</code>, <code>pulseeio</code>, <code>pwmio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgbmatrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharpendisplay</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>zlib</code></td>
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<td>iMX RT 1060 EVK</td>
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Frozen Modules: adafruit_sp32spi, adafruit_requests
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<td>LILYGO TTGO T-01C3</td>
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<td>socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, vectorio, watchdog, wifi, zlib</td>
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<td>LILYGO TTGO T8 ESP32-S2</td>
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<td>LoC BeR M4 base board</td>
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<td>LOLIN S3 16MB Flash 8MB PSRAM</td>
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<td>micro:bit v2</td>
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<td>MicroDev microC3</td>
<td>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, analogio, array, atexit, audiocore, audiomixer, binascii, bitbangio, bitmappools, board, builtins, busio, canio, collections, digitalio, displayio, dotenv, dualbank, ernno, fontio, framebufferio, getpass, hashlib, i2ctarget, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, ps2io, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ubal, vectorio, watchdog, wifi, zlib</td>
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<td>Mini SAM M4</td>
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<td>nanoESP32-S2 w/Wroom</td>
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<td>ndGarage[n°] Bit6:</td>
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<td>FeatherSnow v2</td>
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<td>NUCLEO F446RE</td>
<td>__asyncio. adafruit_bus_device, aesio, analogio, array, atexit, binascii, board, builtins, busio, collections, digitalio, dotenv, ererno, getpass, math, microcontroller, msgpack, onewireio, os, pulseio, pwmio, random, re, rtc, select, storage, struct, supervisor, sys, time, traceback, usb_cdc, zlib</td>
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<td>STM32H743</td>
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<td>Oak Dev Tech</td>
<td>__asyncio, __bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogbufio, analogio, array, atexit, audiobusio, audiocore, audiomixer, audiomp3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, errno, floppyio, fontio, framebufferio, getpass, i2cdriver, imagecapture, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, qrio, rainbowio, random, re, rgmbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zlib</td>
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<td>Oak Dev Tech</td>
<td>__asyncio, __bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, audiomp3, audiopwmio, binascii, bitbangio, bitmaptools, bitops, board, builtins, busio, canio, collections, coproc, countio, digitalio, displayio, dotenv, dualbank, errno, fontio, framebufferio, frequencyio, getpass, gifio, hashlib, i2cdriver, ipaddress, json, keypad, math, mdns, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, ps2io, pulseio, pwmio, qrio, rainbowio, random, re, rgmbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, socketpool, ssl, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, wifi, zlib</td>
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<td>OPENMV-H7 R1</td>
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<td>Particle Argon</td>
<td>_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, alarm, analogio, array, atexit, audiobusio, audiocore, audiomixer, audiomp3, audiopwmio, binascii, bitbangio, bitmaptools, board, builtins, busio, collections, countio, digitalio, displayio, dotenv, errno, fontio, framebufferio, getpass, json, keypad, math, microcontroller, msgpack, neopixel_write, nvm, onewireio, os, paralleldisplay, pulseio, pwmio, rainbowio, random, re, rgbmatrix, rotaryio, rtc, sdcardio, select, sharpdisplay, storage, struct, supervisor, synthio, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, watchdog, zilib</td>
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<td>Particle Xenon</td>
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<td>PewPew 10.2</td>
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<td>Pimoroni Badger 2040</td>
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<td>Pimoroni PicoSystem</td>
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Frozen Modules: stage, ugame

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Table 1 – continued from previous page

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<td>Pimoroni Servo 2040</td>
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<td>Raspberry Pi 4B</td>
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<td>Raspberry Pi Compute Module 4</td>
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<td>Raspberry Pi Pico</td>
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<td>`_asyncio, _bleio, adafruit_bus_device, adafruit_pixelbuf, aesio, array, atexit, binascii, bitbangio, bitmaptools, board, builtins, busio, collections, digitalio, displayio, dotenv, errno, fontio, framebufferio, getpass, json, keypad, math, microcontroller, msgpack, neopixel_write, onewireio, os, rainbowio, random, re, sdcardio, sdioio, select, sharpdisplay, storage, struct, supervisor, sys, terminalio, time, touchio, traceback, ulab, usb_cdc, usb_hid, usb_midi, vectorio, zlib</td>
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<td>Raspberry Pi Zero W</td>
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<td>Robo HAT MM1 M4</td>
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Frozen Modules: neopixel

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<td>adafruit_hid, adafruit_register, neopixel, stamp_carrier_board, stamp_round_carrier_board</td>
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<td>RP2040</td>
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<td>adafruit_hid, adafruit_register, neopixel, stamp_carrier_board, stamp_round_carrier_board</td>
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<td>S2Mini</td>
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Frozen Modules: adafruit_hid, neopixel

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<td><code>_asyncio</code>, <code>_bleio</code>, <code>adafruit_bus_device</code>, <code>adafruit_pixelbuf</code>, <code>aesio</code>, <code>alarm</code>, <code>analogio</code>, <code>array</code>, <code>atexit</code>, <code>audiobusio</code>, <code>audiocore</code>, <code>audiomixer</code>, <code>audiomp3</code>, <code>audiopwmio</code>, <code>binascii</code>, <code>bitbangio</code>, <code>bitmaptools</code>, <code>board</code>, <code>builtins</code>, <code>busio</code>, <code>collections</code>, <code>countio</code>, <code>digitalio</code>, <code>displayio</code>, <code>dotenv</code>, <code>errno</code>, <code>fontio</code>, <code>framebufferio</code>, <code>getpass</code>, <code>json</code>, <code>keypad</code>, <code>math</code>, <code>microcontroller</code>, <code>msgpack</code>, <code>neopixel_write</code>, <code>nvm</code>, <code>onewireio</code>, <code>os</code>, <code>paralleldisplay</code>, <code>pulsiio</code>, <code>pwmio</code>, <code>rainbowio</code>, <code>random</code>, <code>re</code>, <code>rgbmatrix</code>, <code>rotaryio</code>, <code>rtc</code>, <code>sdcardio</code>, <code>select</code>, <code>sharndisplay</code>, <code>storage</code>, <code>struct</code>, <code>supervisor</code>, <code>synthio</code>, <code>sys</code>, <code>terminalio</code>, <code>time</code>, <code>touchio</code>, <code>traceback</code>, <code>ulab</code>, <code>usb_cdc</code>, <code>usb_hid</code>, <code>usb_midi</code>, <code>vectorio</code>, <code>watchdog</code>, <code>zlib</code></td>
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<td>SSCI ISP1807 Micro Board</td>
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<td>stm32f411ce-blackpill-with-flash</td>
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<td>STM32F411E-BLE</td>
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<td>Targett Module Clip w/Wrooom</td>
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<td>Teensy 4.0</td>
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<td>Teensy 4.1</td>
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<td>TG-Watch</td>
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<td>The Open Book Feather</td>
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**Frozen Modules:** neopixel

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## Modules

### _bleio – Bluetooth Low Energy (BLE) communication

The _bleio module provides necessary low-level functionality for communicating using Bluetooth Low Energy (BLE). The ‘_’ prefix indicates this module is meant for internal use by libraries but not by the end user. Its API may change incompatibly between minor versions of CircuitPython. Please use the adafruit_ble CircuitPython library instead, which builds on _bleio, and provides higher-level convenience functionality, including predefined beacons, clients, servers.

**_bleio.adapter :Adapter**

BLE Adapter used to manage device discovery and connections. This object is the sole instance of _bleio.Adapter.

**exception _bleio.BluetoothError**

Bases: Exception

Catchall exception for Bluetooth related errors.

Initialize self. See help(type(self)) for accurate signature.

**exception _bleio.RoleError**

Bases: BluetoothError

Raised when a resource is used as the mismatched role. For example, if a local CCCD is attempted to be set but they can only be set when remote.

Initialize self. See help(type(self)) for accurate signature.

**exception _bleio.SecurityError**

Bases: BluetoothError

Raised when a security related error occurs.
Initialize self. See help(type(self)) for accurate signature.

`_bleio.set_adapter(adapter: Optional[Adapter]) → None`

Set the adapter to use for BLE, such as when using an HCI adapter. Raises `NotImplementedError` when the adapter is a singleton and cannot be set.


The BLE Adapter object manages the discovery and connection to other nearby Bluetooth Low Energy devices. This part of the Bluetooth Low Energy Specification is known as Generic Access Profile (GAP).

Discovery of other devices happens during a scanning process that listens for small packets of information, known as advertisements, that are broadcast unencrypted. The advertising packets have two different uses. The first is to broadcast a small piece of data to anyone who cares and nothing more. These are known as beacons. The second class of advertisement is to promote additional functionality available after the devices establish a connection. For example, a BLE heart rate monitor would advertise that it provides the standard BLE Heart Rate Service.

The Adapter can do both parts of this process: it can scan for other device advertisements and it can advertise its own data. Furthermore, Adapters can accept incoming connections and also initiate connections.

On boards that do not have native BLE, you can use an HCI co-processor. Pass the uart and pins used to communicate with the co-processor, such as an Adafruit AirLift. The co-processor must have been reset and put into BLE mode beforehand by the appropriate pin manipulation. The uart, rts, and cts objects are used to communicate with the HCI co-processor in HCI mode. The `Adapter` object is enabled during this call.

After instantiating an Adapter, call `_bleio.set_adapter()` to set `_bleio.adapter`.

On boards with native BLE, you cannot create an instance of `_bleio.Adapter`; this constructor will raise `NotImplementedError`. Use `_bleio.adapter` to access the sole instance already available.

`enabled : bool`

State of the BLE adapter.

`address : Address`

MAC address of the BLE adapter.

`name : str`

name of the BLE adapter used once connected. The name is “CIRCUITPY” + the last four hex digits of `adapter.address`, to make it easy to distinguish multiple CircuitPython boards.

`advertising : bool`

True when the adapter is currently advertising. (read-only)

`connected : bool`

True when the adapter is connected to another device regardless of who initiated the connection. (read-only)

`connections : Tuple[Connection]`

Tuple of active connections including those initiated through `_bleio.Adapter.connect()`. (read-only)

`start_advertising(data: circuitpython_typing.ReadableBuffer, *, scan_response: Optional[circuitpython_typing.ReadableBuffer] = None, connectable: bool = True, anonymous: bool = False, timeout: int = 0, interval: float = 0.1, tx_power: int = 0, directed_to: Optional[Address] = None) → None`

Starts advertising until `stop_advertising` is called or if connectable, another device connects to us.

**Warning:** If data is longer than 31 bytes, then this will automatically advertise as an extended advertisement that older BLE 4.x clients won’t be able to scan for.
**Note:** If you set `anonymous=True`, then a timeout must be specified. If no timeout is specified, then the maximum allowed timeout will be selected automatically.

**Parameters**

- **data** *(ReadableBuffer)* – advertising data packet bytes
- **scan_response** *(ReadableBuffer)* – scan response data packet bytes. `None` if no scan response is needed.
- **connectable** *(bool)* – If `True` then other devices are allowed to connect to this peripheral.
- **anonymous** *(bool)* – If `True` then this device’s MAC address is randomized before advertising.
- **timeout** *(int)* – If set, we will only advertise for this many seconds. Zero means no timeout.
- **interval** *(float)* – advertising interval, in seconds
- **tx_power** *(int)* – transmitter power while advertising in dBm
- **Address** *(directed_to)* – peer to advertise directly to

**stop_advertising()** → `None`

Stop sending advertising packets.

**start_scan** *(prefixes: circuitpython_typing.ReadableBuffer = b", *, buffer_size: int = 512, extended: bool = False, timeout: Optional[float] = None, interval: float = 0.1, window: float = 0.1, minimum_rssi: int = -80, active: bool = True)* → `Iterable[ScanEntry]`

Starts a BLE scan and returns an iterator of results. Advertisements and scan responses are filtered and returned separately.

**Parameters**

- **prefixes** *(ReadableBuffer)* – Sequence of byte string prefixes to filter advertising packets with. A packet without an advertising structure that matches one of the prefixes is ignored. Format is one byte for length (n) and n bytes of prefix and can be repeated.
- **buffer_size** *(int)* – the maximum number of advertising bytes to buffer.
- **extended** *(bool)* – When True, support extended advertising packets. Increasing buffer_size is recommended when this is set.
- **timeout** *(float)* – the scan timeout in seconds. If None or zero, will scan until stop_scan is called.
- **interval** *(float)* – the interval (in seconds) between the start of two consecutive scan windows Must be in the range 0.0025 - 40.959375 seconds.
- **window** *(float)* – the duration (in seconds) to scan a single BLE channel. window must be <= interval.
- **minimum_rssi** *(int)* – the minimum rssi of entries to return.
- **active** *(bool)* – retrieve scan responses for scannable advertisements.

**Returns**

an iterable of `_bleio.ScanEntry` objects
CircuitPython Documentation, Release 8.0.0-beta.4

Return type
iterable
stop_scan() → None
Stop the current scan.
connect(address: Address, *, timeout: float) → Connection
Attempts a connection to the device with the given address.
Parameters
• address (Address) – The address of the peripheral to connect to
• timeout (float/int) – Try to connect for timeout seconds.
erase_bonding() → None
Erase all bonding information stored in flash memory.
class _bleio.Address(address: circuitpython_typing.ReadableBuffer, address_type: int)
Encapsulates the address of a BLE device.
Create a new Address object encapsulating the address value. The value itself can be one of:
Parameters
• address (ReadableBuffer) – The address value to encapsulate. A buffer object (bytearray,
bytes) of 6 bytes.
• address_type (int) – one of the integer values: PUBLIC, RANDOM_STATIC,
RANDOM_PRIVATE_RESOLVABLE, or RANDOM_PRIVATE_NON_RESOLVABLE.
address_bytes :bytes
The bytes that make up the device address (read-only).
Note that the bytes object returned is in little-endian order: The least significant byte is
address_bytes[0]. So the address will appear to be reversed if you print the raw bytes object. If
you print or use str() on the Attribute object itself, the address will be printed in the expected order.
For example:
>>> import _bleio
>>> _bleio.adapter.address
<Address c8:1d:f5:ed:a8:35>
>>> _bleio.adapter.address.address_bytes
b'5\xa8\xed\xf5\x1d\xc8'
type :int
The address type (read-only).
One of the integer values:
PUBLIC, RANDOM_STATIC, RANDOM_PRIVATE_RESOLVABLE, or
RANDOM_PRIVATE_NON_RESOLVABLE.
PUBLIC :int
A publicly known address, with a company ID (high 24 bits)and company-assigned part (low 24 bits).
RANDOM_STATIC :int
A randomly generated address that does not change often. It may never change or may change after a power
cycle.
RANDOM_PRIVATE_RESOLVABLE :int
An address that is usable when the peer knows the other device’s secret Identity Resolving Key (IRK).

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RANDOM_PRIVATE_NON_RESOLVABLE : int
   A randomly generated address that changes on every connection.

__eq__(other: object) → bool
   Two Address objects are equal if their addresses and address types are equal.

__hash__() → int
   Returns a hash for the Address data.

class _bleio.Attribute
   Definitions associated with all BLE attributes: characteristics, descriptors, etc.

   Attribute is, notionally, a superclass of Characteristic and Descriptor, but is not defined as a Python superclass of those classes.

   You cannot create an instance of Attribute.

NO_ACCESS : int
   security mode: access not allowed

OPEN : int
   security_mode: no security (link is not encrypted)

ENCRYPT_NO_MITM : int
   security_mode: unauthenticated encryption, without man-in-the-middle protection

ENCRYPT_WITH_MITM : int
   security_mode: authenticated encryption, with man-in-the-middle protection

LESC_ENCRYPT_WITH_MITM : int
   security_mode: LESC encryption, with man-in-the-middle protection

SIGNED_NO_MITM : int
   security_mode: unauthenticated data signing, without man-in-the-middle protection

SIGNED_WITH_MITM : int
   security_mode: authenticated data signing, without man-in-the-middle protection

class _bleio.Characteristic
   Stores information about a BLE service characteristic and allows reading and writing of the characteristic’s value.

   There is no regular constructor for a Characteristic. A new local Characteristic can be created and attached to a Service by calling add_to_service(). Remote Characteristic objects are created by Connection.discover_remote_services() as part of remote Services.

   properties : int
      An int bitmask representing which properties are set, specified as bitwise or’ing of of these possible values.

   BROADCAST, INDICATE, NOTIFY, READ, WRITE, WRITE_NO_RESPONSE.

   uuid : Optional[UUID]
      The UUID of this characteristic. (read-only)

      Will be None if the 128-bit UUID for this characteristic is not known.

   value : bytearray
      The value of this characteristic.

   max_length : int
      The max length of this characteristic.
**descriptors**: `Descriptor`  
A tuple of `Descriptor` objects related to this characteristic. (read-only)

**service**: `Service`  
The Service this Characteristic is a part of.

**BROADCAST**: `int`  
property: allowed in advertising packets

**INDICATE**: `int`  
property: server will indicate to the client when the value is set and wait for a response

**NOTIFY**: `int`  
property: server will notify the client when the value is set

**READ**: `int`  
property: clients may read this characteristic

**WRITE**: `int`  
property: clients may write this characteristic; a response will be sent back

**WRITE_NO_RESPONSE**: `int`  
property: clients may write this characteristic; no response will be sent back


Create a new Characteristic object, and add it to this Service.

**Parameters**

- **service** (`Service`) – The service that will provide this characteristic
- **uuid** (`UUID`) – The uuid of the characteristic
- **properties** (`int`) – The properties of the characteristic, specified as a bitmask of these values bitwise-or'd together: `BROADCAST`, `INDICATE`, `NOTIFY`, `READ`, `WRITE`, `WRITE_NO_RESPONSE`.
- **read_perm** (`int`) – Specifies whether the characteristic can be read by a client, and if so, which security mode is required. Must be one of the integer values `Attribute.NO_ACCESS`, `Attribute.OPEN`, `Attribute.ENCRYPT_NO_MITM`, `Attribute.ENCRYPT_WITH_MITM`, `Attribute.LESC_ENCRYPT_WITH_MITM`, or `Attribute.SIGNED_NO_MITM`, or `Attribute.SIGNED_WITH_MITM`.
- **write_perm** (`int`) – Specifies whether the characteristic can be written by a client, and if so, which security mode is required. Values allowed are the same as `read_perm`.
- **max_length** (`int`) – Maximum length in bytes of the characteristic value. The maximum allowed is 512, or possibly 510 if `fixed_length` is False. The default, 20, is the maximum number of data bytes that fit in a single BLE 4.x ATT packet.
- **fixed_length** (`bool`) – True if the characteristic value is of fixed length.
- **initial_value** (`ReadableBuffer`) – The initial value for this characteristic. If not given, will be filled with zeros.
- **user_description** (`str`) – User friendly description of the characteristic
Returns

the new Characteristic.

```python
set_cccd(*, notify: bool = False, indicate: bool = False) → None
```

Set the remote characteristic’s CCCD to enable or disable notification and indication.

**Parameters**

- **notify (bool)** – True if Characteristic should receive notifications of remote writes
- **indicate (float)** – True if Characteristic should receive indications of remote writes

```python
class _bleioCharacteristicBuffer(characteristic: Characteristic, *, timeout: int = 1, buffer_size: int = 64)
```

Accumulates a Characteristic’s incoming values in a FIFO buffer.

Monitor the given Characteristic. Each time a new value is written to the Characteristic add the newly-written bytes to a FIFO buffer.

**Parameters**

- **characteristic (Characteristic)** – The Characteristic to monitor. It may be a local Characteristic provided by a Peripheral Service, or a remote Characteristic in a remote Service that a Central has connected to.
- **timeout (int)** – the timeout in seconds to wait for the first character and between subsequent characters.
- **buffer_size (int)** – Size of ring buffer that stores incoming data coming from client. Must be >= 1.

```python
in_waiting :int
```

The number of bytes in the input buffer, available to be read.

```python
read(nbytes: Optional[int] = None) → Optional[bytes]
```

Read characters. If `nbytes` is specified then read at most that many bytes. Otherwise, read everything that arrives until the connection times out. Providing the number of bytes expected is highly recommended because it will be faster.

Returns

Data read

**Return type**

bytes or None

```python
readinto(buf: circuitpython_typing.WriteableBuffer) → Optional[int]
```

Read bytes into the `buf`. Read at most `len(buf)` bytes.

Returns

number of bytes read and stored into `buf`

**Return type**

int or None (on a non-blocking error)

```python
readline() → bytes
```

Read a line, ending in a newline character.

Returns

the line read

**Return type**

int or None
**reset_input_buffer**() → None
Discard any unread characters in the input buffer.

**deinit**() → None
Disable permanently.

**class** _bleio.Connection
A BLE connection to another device. Used to discover and interact with services on the other device.

*Usage:*

```python
import _bleio

my_entry = None
for entry in _bleio.adapter.scan(2.5):
    if entry.name is not None and entry.name == 'InterestingPeripheral':
        my_entry = entry
        break

if not my_entry:
    raise Exception("InterestingPeripheral not found")

connection = _bleio.adapter.connect(my_entry.address, timeout=10)
```

Connections cannot be made directly. Instead, to initiate a connection use _Adapter.connect_. Connections may also be made when another device initiates a connection. To use a Connection created by a peer, read the _Adapter.connections_ property.

**connected** :bool
True if connected to the remote peer.

**paired** :bool
True if paired to the remote peer.

**connection_interval** :float
Time between transmissions in milliseconds. Will be multiple of 1.25ms. Lower numbers increase speed and decrease latency but increase power consumption.

When setting **connection_interval**, the peer may reject the new interval and **connection_interval** will then remain the same.

Apple has additional guidelines that dictate should be a multiple of 15ms except if HID is available. When HID is available Apple devices may accept 11.25ms intervals.

**max_packet_length** :int
The maximum number of data bytes that can be sent in a single transmission, not including overhead bytes.

This is the maximum number of bytes that can be sent in a notification, which must be sent in a single packet. But for a regular characteristic read or write, may be sent in multiple packets, so this limit does not apply.

**disconnect**() → None
Disconnects from the remote peripheral. Does nothing if already disconnected.

**pair(** *, bond: bool = True **)** → None
Pair to the peer to improve security.
discover_remote_services(service_uuids_whitelist: Optional[Iterable[UUID]] = None) → Tuple[Service, Ellipsis]

Do BLE discovery for all services or for the given service UUIDS, to find their handles and characteristics, and return the discovered services. Connection.connected must be True.

Parameters

service_uuids_whitelist (iterable) – an iterable of UUID objects for the services provided by the peripheral that you want to use.

The peripheral may provide more services, but services not listed are ignored and will not be returned.

If service_uuids_whitelist is None, then all services will undergo discovery, which can be slow.

If the service UUID is 128-bit, or its characteristic UUID’s are 128-bit, you you must have already created a UUID object for that UUID in order for the service or characteristic to be discovered. Creating the UUID causes the UUID to be registered for use. (This restriction may be lifted in the future.)

Returns

A tuple of _bleio.Service objects provided by the remote peripheral.

class _bleio.Descriptor

Stores information about a BLE descriptor.

Descriptors are attached to BLE characteristics and provide contextual information about the characteristic.

There is no regular constructor for a Descriptor. A new local Descriptor can be created and attached to a Characteristic by calling add_to_characteristic(). Remote Descriptor objects are created by Connection.discover_remote_services() as part of remote Characteristics in the remote Services that are discovered.

uuid :UUID

The descriptor uuid. (read-only)

characteristic :Characteristic

The Characteristic this Descriptor is a part of.

value :bytearray

The value of this descriptor.


Create a new Descriptor object, and add it to this Service.

Parameters

• characteristic (Characteristic) – The characteristic that will hold this descriptor

• uuid (UUID) – The uuid of the descriptor

• read_perm (int) – Specifies whether the descriptor can be read by a client, and if so, which security mode is required. Must be one of the integer values Attribute.NO_ACCESS, Attribute.OPEN, Attribute.ENCRYPT_NO_MITM, Attribute.ENCRYPT_WITH_MITM, Attribute.LESC_ENCRYPT_WITH_MITM, Attribute.SIGNED_NO_MITM, or Attribute.SIGNED_WITH_MITM.
- **write_perm (int)** – Specifies whether the descriptor can be written by a client, and if so, which security mode is required. Values allowed are the same as `read_perm`.

- **max_length (int)** – Maximum length in bytes of the descriptor value. The maximum allowed is 512, or possibly 510 if `fixed_length` is False. The default, 20, is the maximum number of data bytes that fit in a single BLE 4.x ATT packet.

- **fixed_length (bool)** – True if the descriptor value is of fixed length.

- **initial_value (ReadableBuffer)** – The initial value for this descriptor.

Returns

the new Descriptor.

class _bleio.PacketBuffer(characteristic: Characteristic, *, buffer_size: int, max_packet_size: Optional[int] = None)

Accumulates a Characteristic’s incoming packets in a FIFO buffer and facilitates packet aware outgoing writes. A packet’s size is either the characteristic length or the maximum transmission unit (MTU) minus overhead, whichever is smaller. The MTU can change so check `incoming_packet_length` and `outgoing_packet_length` before creating a buffer to store data.

When we’re the server, we ignore all connections besides the first to subscribe to notifications.

Monitor the given Characteristic. Each time a new value is written to the Characteristic add the newly-written bytes to a FIFO buffer.

Monitor the given Characteristic. Each time a new value is written to the Characteristic add the newly-written packet of bytes to a FIFO buffer.

Parameters

- **characteristic (Characteristic)** – The Characteristic to monitor. It may be a local Characteristic provided by a Peripheral Service, or a remote Characteristic in a remote Service that a Central has connected to.

- **buffer_size (int)** – Size of ring buffer (in packets of the Characteristic’s maximum length) that stores incoming packets coming from the peer.

- **max_packet_size (int)** – Maximum size of packets. Overrides value from the characteristic. (Remote characteristics may not have the correct length.)

`incoming_packet_length :int`

Maximum length in bytes of a packet we are reading.

`outgoing_packet_length :int`

Maximum length in bytes of a packet we are writing.

`readinto(buf: circuitpython_typing.WriteableBuffer) → int`

Reads a single BLE packet into the buf. Raises an exception if the next packet is longer than the given buffer. Use `incoming_packet_length` to read the maximum length of a single packet.

Returns

number of incoming_packet_length to read the maximum length of a single packet.

`Return type`

int

`write(data: circuitpython_typing.ReadableBuffer, *, header: Optional[bytes] = None) → int`

Writes all bytes from data into the same outgoing packet. The bytes from header are included before data when the pending packet is currently empty.

This does not block until the data is sent. It only blocks until the data is pending.
Returns
class \_bleio.ScanEntry
Encapsulates information about a device that was received during scanning. It can be advertisement or scan response data. This object may only be created by a \_bleio.ScanResults: it has no user-visible constructor. Cannot be instantiated directly. Use \_bleio.Adapter.start_scan.

class \_bleio.ScanResults
Iterates over advertising data received while scanning. This object is always created by a \_bleio.Adapter: it has no user-visible constructor. Cannot be instantiated directly. Use \_bleio.Adapter.start_scan.

class \_bleio.Service
Stores information about a BLE service and its characteristics.

Parameters

- **uuid (UUID)** – The uuid of the service
- **secondary (bool)** – If the service is a secondary one
Returns
the new Service

`characteristics :Tuple[Characteristic, Ellipsis]`
A tuple of `Characteristic` designating the characteristics that are offered by this service. (read-only)

`remote :bool`
True if this is a service provided by a remote device. (read-only)

`secondary :bool`
True if this is a secondary service. (read-only)

`uuid :Optional[UUID]`
The UUID of this service. (read-only)
Will be `None` if the 128-bit UUID for this service is not known.

class `bleio.UUID`(`value: Union[int, circuitpython_typing.ReadableBuffer, str]`)  
A 16-bit or 128-bit UUID. Can be used for services, characteristics, descriptors and more.

Create a new UUID or UUID object encapsulating the `uuid` value. The value can be one of:
- an `int` value in range 0 to 0xFFFF (Bluetooth SIG 16-bit UUID)
- a buffer object (bytearray, bytes) of 16 bytes in little-endian order (128-bit UUID)
- a string of hex digits of the form ‘xxxxxxxx-xxxx-xxxx-xxxx-xxxxxxxxxxxx’

Creating a 128-bit UUID registers the UUID with the onboard BLE software, and provides a temporary 16-bit UUID that can be used in place of the full 128-bit UUID.

Parameters
`value (int, ReadableBuffer or str) – The `uuid` value to encapsulate`

`uuid16 :int`
The 16-bit part of the UUID. (read-only)

Type
`int`

`uuid128 :bytes`
The 128-bit value of the UUID Raises AttributeError if this is a 16-bit UUID. (read-only)

Type
`bytes`

`size :int`
128 if this UUID represents a 128-bit vendor-specific UUID. 16 if this UUID represents a 16-bit Bluetooth SIG assigned UUID. (read-only) 32-bit UUIDs are not currently supported.

Type
`int`

`pack_into(buffer: circuitpython_typing.WriteableBuffer, offset: int = 0) → None`
Packs the UUID into the given buffer at the given offset.

`__eq__(other: object) → bool`
Two UUID objects are equal if their values match and they are both 128-bit or both 16-bit.
**_eve – Low-level BridgeTek EVE bindings**

The _eve module provides a class _EVE which contains methods for constructing EVE command buffers and appending basic graphics commands.

**class _eve._EVE**

Create an _EVE object

```python
register(o: object) → None
```

**flush() → None**

Send any queued drawing commands directly to the hardware.

Parameters

- **width (int)** – The width of the grid in tiles, or 1 for sprites.

**cc(b: circuitpython_typing.ReadableBuffer) → None**

Append bytes to the command FIFO.

Parameters

- **b (ReadableBuffer)** – The bytes to add

**AlphaFunc(func: int, ref: int) → None**

Set the alpha test function

Parameters

- **func (int)** – specifies the test function, one of NEVER, LESS, LEQUAL, GREATER, GEQUAL, EQUAL, NOTEQUAL, or ALWAYS. Range 0-7. The initial value is ALWAYS(7)
- **ref (int)** – specifies the reference value for the alpha test. Range 0-255. The initial value is 0.

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**Begin(prim: int) → None**

Begin drawing a graphics primitive

Parameters

- **prim (int)** – graphics primitive.

Valid primitives are BITMAPS, POINTS, LINES, LINE_STRIP, EDGE_STRIP_R, EDGE_STRIP_L, EDGE_STRIP_A, EDGE_STRIP_B and RECTS.

**BitmapExtFormat(format: int) → None**

Set the bitmap format

Parameters

- **format (int)** – bitmap pixel format.

**BitmapHandle(handle: int) → None**

Set the bitmap handle

Parameters

- **handle (int)** – bitmap handle. Range 0-31. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.
BitmapLayoutH(linestride: int, height: int) → None
Set the source bitmap memory format and layout for the current handle. high bits for large bitmaps

Parameters
• linestride (int) – high part of bitmap line stride, in bytes. Range 0-7
• height (int) – high part of bitmap height, in lines. Range 0-3

BitmapLayout(format: int, linestride: int, height: int) → None
Set the source bitmap memory format and layout for the current handle

Parameters
• format (int) – bitmap pixel format, or GLFORMAT to use BITMAP_EXT_FORMAT instead. Range 0-31
• linestride (int) – bitmap line stride, in bytes. Range 0-1023
• height (int) – bitmap height, in lines. Range 0-511

BitmapSizeH(width: int, height: int) → None
Set the screen drawing of bitmaps for the current handle. high bits for large bitmaps

Parameters
• width (int) – high part of drawn bitmap width, in pixels. Range 0-3
• height (int) – high part of drawn bitmap height, in pixels. Range 0-3

BitmapSize(filter: int, wrapx: int, wrapy: int, width: int, height: int) → None
Set the screen drawing of bitmaps for the current handle

Parameters
• filter (int) – bitmap filtering mode, one of NEAREST or BILINEAR. Range 0-1
• wrapx (int) – bitmap x wrap mode, one of REPEAT or BORDER. Range 0-1
• wrapy (int) – bitmap y wrap mode, one of REPEAT or BORDER. Range 0-1
• width (int) – drawn bitmap width, in pixels. Range 0-511
• height (int) – drawn bitmap height, in pixels. Range 0-511

BitmapSource(addr: int) → None
Set the source address for bitmap graphics

Parameters
addr (int) – Bitmap start address, pixel-aligned. May be in SRAM or flash. Range 0-16777215

BitmapSwizzle(r: int, g: int, b: int, a: int) → None
Set the source for the r,g,b and a channels of a bitmap

Parameters
• r (int) – red component source channel. Range 0-7
• g (int) – green component source channel. Range 0-7
• b (int) – blue component source channel. Range 0-7
• a (int) – alpha component source channel. Range 0-7
**BitmapTransformA** $(p: \text{int}, v: \text{int}) \rightarrow \text{None}$

Set the $a$ component of the bitmap transform matrix

**Parameters**

- $p$ (int) – precision control: 0 is 8.8, 1 is 1.15. Range 0-1. The initial value is 0
- $v$ (int) – The $a$ component of the bitmap transform matrix, in signed 8.8 or 1.15 bit fixed-point form. Range 0-131071. The initial value is 256

The initial value is $p = 0, v = 256$. This represents the value 1.0.

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**BitmapTransformB** $(p: \text{int}, v: \text{int}) \rightarrow \text{None}$

Set the $b$ component of the bitmap transform matrix

**Parameters**

- $p$ (int) – precision control: 0 is 8.8, 1 is 1.15. Range 0-1. The initial value is 0
- $v$ (int) – The $b$ component of the bitmap transform matrix, in signed 8.8 or 1.15 bit fixed-point form. Range 0-131071. The initial value is 0

The initial value is $p = 0, v = 0$. This represents the value 0.0.

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**BitmapTransformC** $(v: \text{int}) \rightarrow \text{None}$

Set the $c$ component of the bitmap transform matrix

**Parameters**

- $v$ (int) – The $c$ component of the bitmap transform matrix, in signed 15.8 bit fixed-point form. Range 0-16777215. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**BitmapTransformD** $(p: \text{int}, v: \text{int}) \rightarrow \text{None}$

Set the $d$ component of the bitmap transform matrix

**Parameters**

- $p$ (int) – precision control: 0 is 8.8, 1 is 1.15. Range 0-1. The initial value is 0
- $v$ (int) – The $d$ component of the bitmap transform matrix, in signed 8.8 or 1.15 bit fixed-point form. Range 0-131071. The initial value is 0

The initial value is $p = 0, v = 0$. This represents the value 0.0.

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**BitmapTransformE** $(p: \text{int}, v: \text{int}) \rightarrow \text{None}$

Set the $e$ component of the bitmap transform matrix

**Parameters**

- $p$ (int) – precision control: 0 is 8.8, 1 is 1.15. Range 0-1. The initial value is 0
- $v$ (int) – The $e$ component of the bitmap transform matrix, in signed 8.8 or 1.15 bit fixed-point form. Range 0-131071. The initial value is 256
The initial value is \( p = 0, \ v = 256 \). This represents the value 1.0.

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**BitmapTransformF** \( (v: \text{int}) \to \text{None} \)

Set the \( f \) component of the bitmap transform matrix

**Parameters**

\( v \ (\text{int}) \) – The \( f \) component of the bitmap transform matrix, in signed 15.8 bit fixed-point form. Range 0-16777215. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**BlendFunc** \( (\text{src: int, dst: int}) \to \text{None} \)

Set pixel arithmetic

**Parameters**

• \text{src} (\text{int}) – specifies how the source blending factor is computed. One of \text{ZERO}, \text{ONE}, \text{SRC_ALPHA}, \text{DST_ALPHA}, \text{ONE_MINUS_SRC_ALPHA} or \text{ONE_MINUS_DST_ALPHA}. Range 0-7. The initial value is SRC_ALPHA(2)

• \text{dst} (\text{int}) – specifies how the destination blending factor is computed, one of the same constants as \text{src}. Range 0-7. The initial value is ONE_MINUS_SRC_ALPHA(4)

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**Call** \( (\text{dest: int}) \to \text{None} \)

Execute a sequence of commands at another location in the display list

**Parameters**

\text{dest} (\text{int}) – display list address. Range 0-65535

**Cell** \( (\text{cell: int}) \to \text{None} \)

Set the bitmap cell number for the vertex2f command

**Parameters**

\text{cell} (\text{int}) – bitmap cell number. Range 0-127. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**ClearColorA** \( (\text{alpha: int}) \to \text{None} \)

Set clear value for the alpha channel

**Parameters**

\text{alpha} (\text{int}) – alpha value used when the color buffer is cleared. Range 0-255. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**ClearColorRGB** \( (\text{red: int, green: int, blue: int}) \to \text{None} \)

Set clear values for red, green and blue channels

**Parameters**

• \text{red} (\text{int}) – red value used when the color buffer is cleared. Range 0-255. The initial value is 0
• **green** (*int*) – green value used when the color buffer is cleared. Range 0-255. The initial value is 0

• **blue** (*int*) – blue value used when the color buffer is cleared. Range 0-255. The initial value is 0

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**Clear** (*c: int, s: int, t: int*) → None

Clear buffers to preset values

**Parameters**

• **c** (*int*) – clear color buffer. Range 0-1

• **s** (*int*) – clear stencil buffer. Range 0-1

• **t** (*int*) – clear tag buffer. Range 0-1

**ClearStencil** (*s: int*) → None

Set clear value for the stencil buffer

**Parameters**

• **s** (*int*) – value used when the stencil buffer is cleared. Range 0-255. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**ClearTag** (*s: int*) → None

Set clear value for the tag buffer

**Parameters**

• **s** (*int*) – value used when the tag buffer is cleared. Range 0-255. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**ColorA** (*alpha: int*) → None

Set the current color alpha

**Parameters**

• **alpha** (*int*) – alpha for the current color. Range 0-255. The initial value is 255

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**ColorMask** (*r: int, g: int, b: int, a: int*) → None

Enable and disable writing of frame buffer color components

**Parameters**

• **r** (*int*) – allow updates to the frame buffer red component. Range 0-1. The initial value is 1

• **g** (*int*) – allow updates to the frame buffer green component. Range 0-1. The initial value is 1

• **b** (*int*) – allow updates to the frame buffer blue component. Range 0-1. The initial value is 1

• **a** (*int*) – allow updates to the frame buffer alpha component. Range 0-1. The initial value is 1
These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**ColorRGB(red: int, green: int, blue: int) → None**

Set the drawing color

*Parameters*

- **red(int)** – red value for the current color. Range 0-255. The initial value is 255
- **green(int)** – green for the current color. Range 0-255. The initial value is 255
- **blue(int)** – blue for the current color. Range 0-255. The initial value is 255

These values are part of the graphics context and are saved and restored by `SaveContext()` and `RestoreContext()`.

**Display() → None**

End the display list

**End() → None**

End drawing a graphics primitive

*Vertex2ii()* and *Vertex2f()* calls are ignored until the next *Begin()*.

**Jump(dest: int) → None**

Execute commands at another location in the display list

*Parameters*

- **dest(int)** – display list address. Range 0-65535

**Macro(m: int) → None**

Execute a single command from a macro register

*Parameters*

- **m(int)** – macro register to read. Range 0-1

**Nop() → None**

No operation

**PaletteSource(addr: int) → None**

Set the base address of the palette

*Parameters*

- **addr(int)** – Address in graphics SRAM, 2-byte aligned. Range 0-4194303. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**RestoreContext() → None**

Restore the current graphics context from the context stack

**Return() → None**

Return from a previous call command

**SaveContext() → None**

Push the current graphics context on the context stack
**ScissorSize** \( (\text{width: int, height: int}) \rightarrow \text{None} \)

Set the size of the scissor clip rectangle

**Parameters**

- **width** (int) – The width of the scissor clip rectangle, in pixels. Range 0-4095. The initial value is hsize
- **height** (int) – The height of the scissor clip rectangle, in pixels. Range 0-4095. The initial value is 2048

These values are part of the graphics context and are saved and restored by **SaveContext**() and **RestoreContext**().

**ScissorXY** \( (x: int, y: int) \rightarrow \text{None} \)

Set the top left corner of the scissor clip rectangle

**Parameters**

- **x** (int) – The x coordinate of the scissor clip rectangle, in pixels. Range 0-2047. The initial value is 0
- **y** (int) – The y coordinate of the scissor clip rectangle, in pixels. Range 0-2047. The initial value is 0

These values are part of the graphics context and are saved and restored by **SaveContext**() and **RestoreContext**().

**StencilFunc** \( (\text{func: int, ref: int, mask: int}) \rightarrow \text{None} \)

Set function and reference value for stencil testing

**Parameters**

- **func** (int) – specifies the test function, one of NEVER, LESS, LEQUAL, GREATER, GEQUAL, EQUAL, NOTEQUAL, or ALWAYS. Range 0-7. The initial value is ALWAYS(7)
- **ref** (int) – specifies the reference value for the stencil test. Range 0-255. The initial value is 0
- **mask** (int) – specifies a mask that is ANDed with the reference value and the stored stencil value. Range 0-255. The initial value is 255

These values are part of the graphics context and are saved and restored by **SaveContext**() and **RestoreContext**().

**StencilMask** \( (\text{mask: int}) \rightarrow \text{None} \)

Control the writing of individual bits in the stencil planes

**Parameters**

- **mask** (int) – the mask used to enable writing stencil bits. Range 0-255. The initial value is 255

This value is part of the graphics context and is saved and restored by **SaveContext**() and **RestoreContext**().

**StencilOp** \( (\text{sfail: int, spass: int}) \rightarrow \text{None} \)

Set stencil test actions

**Parameters**

- **sfail** (int) – specifies the action to take when the stencil test fails, one of KEEP, ZERO, REPLACE, INCR, INCR_WRAP, DECR, DECR_WRAP, and INVERT. Range 0-7. The initial value is KEEP(1)
• spass (int) – specifies the action to take when the stencil test passes, one of the same constants as sfail. Range 0-7. The initial value is KEEP(1)

These values are part of the graphics context and are saved and restored by \texttt{SaveContext()} and \texttt{RestoreContext()}.

\textbf{TagMask}(mask: int) \rightarrow None

Control the writing of the tag buffer

\hspace{1em} Parameters

\hspace{2em} mask (int) – allow updates to the tag buffer. Range 0-1. The initial value is 1

This value is part of the graphics context and is saved and restored by \texttt{SaveContext()} and \texttt{RestoreContext()}.

\textbf{Tag}(s: int) \rightarrow None

Set the current tag value

\hspace{1em} Parameters

\hspace{2em} s (int) – tag value. Range 0-255. The initial value is 255

This value is part of the graphics context and is saved and restored by \texttt{SaveContext()} and \texttt{RestoreContext()}.

\textbf{Vertex2ii}(x: int, y: int, handle: int, cell: int) \rightarrow None

\hspace{1em} Parameters

\hspace{2em} x (int) – x-coordinate in pixels. Range 0-511

\hspace{2em} y (int) – y-coordinate in pixels. Range 0-511

\hspace{2em} handle (int) – bitmap handle. Range 0-31

\hspace{2em} cell (int) – cell number. Range 0-127

This method is an alternative to \texttt{Vertex2f()}

\textbf{Vertex2f}(b: float) \rightarrow None

Draw a point.

\hspace{1em} Parameters

\hspace{2em} x (float) – pixel x-coordinate

\hspace{2em} y (float) – pixel y-coordinate

\textbf{LineWidth}(width: float) \rightarrow None

Set the width of rasterized lines

\hspace{1em} Parameters

\hspace{2em} width (float) – line width in pixels. Range 0-511. The initial value is 1

This value is part of the graphics context and is saved and restored by \texttt{SaveContext()} and \texttt{RestoreContext()}.

\textbf{PointSize}(size: float) \rightarrow None

Set the diameter of rasterized points

\hspace{1em} Parameters

\hspace{2em} size (float) – point diameter in pixels. Range 0-1023. The initial value is 1

This value is part of the graphics context and is saved and restored by \texttt{SaveContext()} and \texttt{RestoreContext()}.
**VertexTranslateX**

Set the vertex transformation’s x translation component

**Parameters**

\( x \) (float) – signed x-coordinate in pixels. Range ±4095. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**VertexTranslateY**

Set the vertex transformation’s y translation component

**Parameters**

\( y \) (float) – signed y-coordinate in pixels. Range ±4095. The initial value is 0

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**VertexFormat**

Set the precision of vertex2f coordinates

**Parameters**

\( \text{frac} \) (int) – Number of fractional bits in X,Y coordinates, 0-4. Range 0-7. The initial value is 4

This value is part of the graphics context and is saved and restored by `SaveContext()` and `RestoreContext()`.

**cmd0**

Append the command word n to the FIFO

**Parameters**

\( n \) (int) – The command code

This method is used by the `eve` module to efficiently add commands to the FIFO.

**cmd**

Append a command packet to the FIFO.

**Parameters**

- \( n \) (int) – The command code
- \( fmt \) (str) – The command format `struct` layout
- \( \text{args} \) (tuple(str, ...)) – The command’s arguments

Supported format codes: h, H, i, I.

This method is used by the `eve` module to efficiently add commands to the FIFO.

**_pew – LED matrix driver**

**class _pew.PewPew**

This is an internal module to be used by the `pew.py` library from [https://github.com/pewpew-game/pew-pewpew-standalone-10.x](https://github.com/pewpew-game/pew-pewpew-standalone-10.x) to handle the LED matrix display and buttons on the `pewpew10` board.

**Usage:**
This singleton class is instantiated by the `pew` library, and used internally by it. All user-visible interactions are done through that library.

Initializes matrix scanning routines.

The `buffer` is a 64 byte long `bytearray` that stores what should be displayed on the matrix. `rows` and `cols` are both lists of eight `DigitalInputOutput` objects that are connected to the matrix rows and columns. `buttons` is a `DigitalInputOutput` object that is connected to the common side of all buttons (the other sides of the buttons are connected to rows of the matrix).

`_stage` – C-level helpers for animation of sprites on a stage

The `_stage` module contains native code to speed-up the `stage Library <https://github.com/python-ugame/circuitpython-stage>`.

```
*_stage.render*(x0: int, y0: int, x1: int, y1: int, layers: List[Layer], buffer: circuitpython_typing.WriteableBuffer, display: displayio.Display, scale: int, background: int) → None
```

Render and send to the display a fragment of the screen.

**Parameters**

- `x0` (*int*) – Left edge of the fragment.
- `y0` (*int*) – Top edge of the fragment.
- `x1` (*int*) – Right edge of the fragment.
- `y1` (*int*) – Bottom edge of the fragment.
- `layers` (*list[Layer]*) – A list of the `Layer` objects.
- `buffer` (*ReadableBuffer*) – A buffer to use for rendering.
- `display` (*Display*) – The display to use.
- `scale` (*int*) – How many times should the image be scaled up.
- `background` (*int*) – What color to display when nothing is there.

There are also no sanity checks, outside of the basic overflow checking. The caller is responsible for making the passed parameters valid.

This function is intended for internal use in the `stage` library and all the necessary checks are performed there.

```
```

Keep information about a single layer of graphics

Keep internal information about a layer of graphics (either a `Grid` or a `Sprite`) in a format suitable for fast rendering with the `render()` function.

**Parameters**

- `width` (*int*) – The width of the grid in tiles, or 1 for sprites.
- `height` (*int*) – The height of the grid in tiles, or 1 for sprites.
- `graphic` (*ReadableBuffer*) – The graphic data of the tiles.
- `palette` (*ReadableBuffer*) – The color palette to be used.
- `grid` (*ReadableBuffer*) – The contents of the grid map.
This class is intended for internal use in the stage library and it shouldn’t be used on its own.

move\((x: \text{ int}, y: \text{ int}) \to \text{None}\)
Set the offset of the layer to the specified values.

frame\((frame: \text{ int}, rotation: \text{ int}) \to \text{None}\)
Set the animation frame of the sprite, and optionally rotation its graphic.

Keep information about a single grid of text
Keep internal information about a grid of text in a format suitable for fast rendering with the render() function.

Parameters

• width (int) – The width of the grid in tiles, or 1 for sprites.
• height (int) – The height of the grid in tiles, or 1 for sprites.
• font (ReadableBuffer) – The font data of the characters.
• palette (ReadableBuffer) – The color palette to be used.
• chars (ReadableBuffer) – The contents of the character grid.

This class is intended for internal use in the stage library and it shouldn’t be used on its own.

move\((x: \text{ int}, y: \text{ int}) \to \text{None}\)
Set the offset of the text to the specified values.

adafruit_bus_device – Hardware accelerated external bus access

The I2CDevice and SPIDevice helper classes make managing transaction state on a bus easy. For example, they manage locking the bus to prevent other concurrent access. For SPI devices, it manages the chip select and protocol changes such as mode. For I2C, it manages the device address.

adafruit_bus_device.i2c_device – I2C Device Manager

class adafruit_bus_device.i2c_device.I2CDevice\((\text{i2c: busio.I2C, device_address: int, probe: bool = True})\)
Represents a single I2C device and manages locking the bus and the device address.

Parameters

• i2c (I2C) – The I2C bus the device is on
• device_address (int) – The 7 bit device address
• probe (bool) – Probe for the device upon object creation, default is true

Example:

```python
import busio
from board import *
from adafruit_bus_device.i2c_device import I2CDevice
with busio.I2C(SCL, SDA) as i2c:
    device = I2CDevice(i2c, 0x70)
```

(continues on next page)
bytes_read = bytearray(4)
with device:
    device.readinto(bytes_read)
# A second transaction
with device:
    device.write(bytes_read)

__enter__() → I2CDevice
Context manager entry to lock bus.

__exit__() → None
Automatically unlocks the bus on exit.

readinto(buffer: circuitpython_typing.WriteableBuffer, *, start: int = 0, end: int = sys.maxsize) → None
Read into buffer from the device.
If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed. The number of bytes read will be the length of buffer[start:end].

Parameters
• buffer (WriteableBuffer) – read bytes into this buffer
• start (int) – beginning of buffer slice
• end (int) – end of buffer slice; if not specified, use len(buffer)

write(buffer: circuitpython_typing.ReadableBuffer, *, start: int = 0, end: int = sys.maxsize) → None
Write the bytes from buffer to the device, then transmit a stop bit.
If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed, but without copying the data. The number of bytes written will be the length of buffer[start:end].

Parameters
• buffer (ReadableBuffer) – write out bytes from this buffer
• start (int) – beginning of buffer slice
• end (int) – end of buffer slice; if not specified, use len(buffer)

write_then_readinto(out_buffer: circuitpython_typing.ReadableBuffer, in_buffer:
circuitpython_typing.WriteableBuffer, *, out_start: int = 0, out_end: int =
sys.maxsize, in_start: int = 0, in_end: int = sys.maxsize) → None
Write the bytes from out_buffer to the device, then immediately reads into in_buffer from the device.
If out_start or out_end is provided, then the buffer will be sliced as if out_buffer[out_start:out_end] were passed, but without copying the data. The number of bytes written will be the length of out_buffer[out_start:out_end].
If in_start or in_end is provided, then the input buffer will be sliced as if in_buffer[in_start:in_end] were passed. The number of bytes read will be the length of out_buffer[in_start:in_end].

Parameters
• out_buffer (ReadableBuffer) – write out bytes from this buffer
• in_buffer (WriteableBuffer) – read bytes into this buffer
• out_start (int) – beginning of out_buffer slice
• **out_end** (*int*) – end of `out_buffer` slice; if not specified, use `len(out_buffer)`
• **in_start** (*int*) – beginning of `in_buffer` slice
• **in_end** (*int*) – end of `in_buffer` slice; if not specified, use `len(in_buffer)`

**adafruit_bus_device.spi_device – SPI Device Manager**

class adafruit_bus_device.spi_device.SPIDevice(spi: `busio.SPI`, chip_select: `digitalio.DigitalInOut`, *,
    baudrate: *int* = 100000, polarity: *int* = 0, phase: *int* = 0, extra_clocks: *int* = 0)

Represents a single SPI device and manages locking the bus and the device address.

**Parameters**

• **spi** (*SPI*) – The SPI bus the device is on
• **chip_select** (*DigitalInOut*) – The chip select pin object that implements the DigitalInOut API.
• **cs_active_value** (*bool*) – Set to true if your device requires CS to be active high. Defaults to false.
• **extra_clocks** (*int*) – The minimum number of clock cycles to cycle the bus after CS is high. (Used for SD cards.)

**Example:**

```python
import busio
import digitalio
from board import *
from adafruit_bus_device.spi_device import SPIDevice

with busio.SPI(SCK, MOSI, MISO) as spi_bus:
    cs = digitalio.DigitalInOut(D10)
    device = SPIDevice(spi_bus, cs)
    bytes_read = bytearray(4)
    # The object assigned to spi in the with statements below
    # is the original spi_bus object. We are using the busio.SPI
    # operations busio.SPI.readinto() and busio.SPI.write().
    with device as spi:
        spi.readinto(bytes_read)
    # A second transaction
    with device as spi:
        spi.write(bytes_read)
```

**__enter__**() → `busio.SPI`

Starts a SPI transaction by configuring the SPI and asserting chip select.

**__exit__**() → None

Ends a SPI transaction by deasserting chip select. See *Lifetime and Context Managers* for more info.
**adafruit_pixelbuf** – A fast RGB(W) pixel buffer library for like NeoPixel and DotStar

The `adafruit_pixelbuf` module provides the `PixelBuf` class to accelerate RGB(W) strip/matrix manipulation, such as DotStar and Neopixel.

Byteorders are configured with strings, such as “RGB” or “RGBD”.

```python
```

A fast RGB[W] pixel buffer for LED and similar devices.

Create a `PixelBuf` object of the specified size, byteorder, and bits per pixel.

When brightness is less than 1.0, a second buffer will be used to store the color values before they are adjusted for brightness.

When P (PWM duration) is present as the 4th character of the byteorder string, the 4th value in the tuple/list for a pixel is the individual pixel brightness (0.0-1.0) and will enable a Dotstar compatible 1st byte for each pixel.

**Parameters**

- `size` *(int)* – Number of pixels
- `byteorder` *(str)* – Byte order string (such as “RGB”, “RGBW” or “PBGR”)
- `brightness` *(float)* – Brightness (0 to 1.0, default 1.0)
- `auto_write` *(bool)* – Whether to automatically write pixels (Default False)
- `header` *(ReadableBuffer)* – Sequence of bytes to always send before pixel values.
- `trailer` *(ReadableBuffer)* – Sequence of bytes to always send after pixel values.

**Methods**

- `bpp :int`
  The number of bytes per pixel in the buffer (read-only)

- `brightness :float`
  Float value between 0 and 1. Output brightness.
  
  When brightness is less than 1.0, a second buffer will be used to store the color values before they are adjusted for brightness.

- `auto_write :bool`
  Whether to automatically write the pixels after each update.

- `byteorder :str`
  Byteorder string for the buffer (read-only)

- `show() → None`
  Transmits the color data to the pixels so that they are shown. This is done automatically when `auto_write` is True.

- `fill(color: Union[int, Tuple[int, int, int], Tuple[int, int, int, float]]) → None`
  Fills the given pixelbuf with the given color.

- `__getitem__(index: slice) → Union[Tuple[Tuple[int, int, int], Ellipsis], Tuple[Tuple[int, int, int, float], Ellipsis]]`

- `__getitem__(index: int) → Union[Tuple[int, int, int], Tuple[int, int, int, float]]`
  Returns the pixel value at the given index as a tuple of (Red, Green, Blue[, White]) values between 0 and 255. When in PWM (DotStar) mode, the 4th tuple value is a float of the pixel intensity from 0-1.0.
__setitem__(index: slice, value: Tuple[Union[int, Tuple[float, Ellipsis], List[float]], Ellipsis]) → None

__setitem__(index: slice, value: List[Union[int, Tuple[float, Ellipsis], List[float]]]) → None

__setitem__(index: int, value: Union[int, Tuple[float, Ellipsis], List[float]]) → None

Sets the pixel value at the given index. Value can either be a tuple or integer. Tuples are The individual (Red, Green, Blue[, White]) values between 0 and 255. If given an integer, the red, green and blue values are packed into the lower three bytes (0xRRGGBB). For RGBW byteorders, if given only RGB values either as an int or as a tuple, the white value is used instead when the red, green, and blue values are the same.

**aesio – AES encryption routines**

The AES module contains classes used to implement encryption and decryption. It aims to be low overhead in terms of memory.

For more information on AES, refer to the Wikipedia entry.

```python
aesio.MODE_ECB : int

aesio.MODE_CBC : int

aesio.MODE_CTR : int

class aesio.AES(key: circuitpython_typing.ReadableBuffer, mode: int = 0, iv: Optional[circuitpython_typing.ReadableBuffer] = None, segment_size: int = 8)

Encrypt and decrypt AES streams

Create a new AES state with the given key.

**Parameters**

- **key** *(ReadableBuffer)* – A 16-, 24-, or 32-byte key
- **mode** *(int)* – AES mode to use. One of: MODE_ECB, MODE_CBC, or MODE_CTR
- **iv** *(ReadableBuffer)* – Initialization vector to use for CBC or CTR mode

Additional arguments are supported for legacy reasons.

Encrypting a string:

```python
import aesio
from binascii import hexlify

key = b'Sixteen byte key'
inp = b'CircuitPython!!'  # Note: 16-bytes long
outp = bytearray(len(inp))
cipher = aesio.AES(key, aesio.MODE_ECB)
cipher.encrypt_into(inp, outp)
hexlify(outp)
```

**encrypt_into**(src: circuitpython_typing.ReadableBuffer, dest: circuitpython_typing.WriteableBuffer) →

Encrypt the buffer from src into dest.

For ECB mode, the buffers must be 16 bytes long. For CBC mode, the buffers must be a multiple of 16 bytes, and must be equal length. For CTX mode, there are no restrictions.
decrypt_into(src: circuitpython_typing.ReadableBuffer, dest: circuitpython_typing.WriteableBuffer) \rightarrow None

Decrypt the buffer from src into dest. For ECB mode, the buffers must be 16 bytes long. For CBC mode, the buffers must be a multiple of 16 bytes, and must be equal length. For CTX mode, there are no restrictions.

alarm – Alarms and sleep

Provides alarms that trigger based on time intervals or on external events, such as pin changes. The program can simply wait for these alarms, or go to sleep and be awoken when they trigger.

There are two supported levels of sleep: light sleep and deep sleep.

Light sleep keeps sufficient state so the program can resume after sleeping. It does not shut down WiFi, BLE, or other communications, or ongoing activities such as audio playback. It reduces power consumption to the extent possible that leaves these continuing activities running. In some cases there may be no decrease in power consumption.

Deep sleep shuts down power to nearly all of the microcontroller including the CPU and RAM. This can save a more significant amount of power, but CircuitPython must restart code.py from the beginning when awakened.

For both light sleep and deep sleep, if CircuitPython is connected to a host computer, maintaining the connection takes priority and power consumption may not be reduced.

For more information about working with alarms and light/deep sleep in CircuitPython, see this Learn guide.

alarm.coproc – Trigger an alarm when another core or co-processor requests wake-up.

class alarm.coproc.CoprocAlarm(coproc: CoprocAlarm.__init__.coproc)

Create an alarm that will be triggered when the co-processor requests wake-up.

The alarm is not active until it is passed to an alarm-enabling function, such as alarm.light_sleep_until_alarms() or alarm.exit_and_deep_sleep_until_alarms().

Parameters
- coproc (coproc.Coproc) – The coproc program to run.

alarm.pin – Trigger an alarm when a pin changes state.

class alarm.pin.PinAlarm(pin: microcontroller.Pin, value: bool, edge: bool = False, pull: bool = False)

Create an alarm triggered by a microcontroller.Pin level. The alarm is not active until it is passed to an alarm-enabling function, such as alarm.light_sleep_until_alarms() or alarm.exit_and_deep_sleep_until_alarms().

Parameters
- pin (microcontroller.Pin) – The pin to monitor. On some ports, the choice of pin may be limited due to hardware restrictions, particularly for deep-sleep alarms.
- value (bool) – When active, trigger when the pin value is high (True) or low (False). On some ports, multiple PinAlarm objects may need to have coordinated values for deep-sleep alarms.
- edge (bool) – If True, trigger only when there is a transition to the specified value of value. If True, if the alarm becomes active when the pin value already matches value, the alarm is not triggered: the pin must transition from not value to value to trigger the alarm. On some ports, edge-triggering may not be available, particularly for deep-sleep alarms.
• **pull (bool)** – Enable a pull-up or pull-down which pulls the pin to the level opposite that of value. For instance, if value is set to True, setting pull to True will enable a pull-down, to hold the pin low normally until an outside signal pulls it high.

```python
circuitcontrol_pin :microcontroller.Pin
The trigger pin.

circuitcontrol_value :bool
The value on which to trigger.
```

**alarm.time** – Trigger an alarm when the specified time is reached.

class alarm.time.TimeAlarm(monotonic_time: Optional[float] = None, epoch_time: Optional[int] = None)
Create an alarm that will be triggered when `time.monotonic()` would equal `monotonic_time`, or when `time.time()` would equal `epoch_time`. Only one of the two arguments can be given. The alarm is not active until it is passed to an alarm-enabling function, such as `alarm.light_sleep_until_alarms()` or `alarm.exit_and_deep_sleep_until_alarms()`.

If the given time is in the past when sleep occurs, the alarm will be triggered immediately.

```python
circuitcontrol_monotonic_time :float
When this time is reached, the alarm will trigger, based on the `time.monotonic()` clock. The time may be given as `epoch_time` in the constructor, but it is returned by this property only as a `time.monotonic()` time.
```

**alarm.touch** – Trigger an alarm when touch is detected.

class alarm.touch.TouchAlarm(*pin: microcontroller.Pin)
Create an alarm that will be triggered when the given pin is touched. The alarm is not active until it is passed to an alarm-enabling function, such as `alarm.light_sleep_until_alarms()` or `alarm.exit_and_deep_sleep_until_alarms()`.

```python
Parameters

circuitcontrol_pin (microcontroller.Pin) – The pin to monitor. On some ports, the choice of pin may be limited due to hardware restrictions, particularly for deep-sleep alarms.
```

**alarm.sleep_memory** :SleepMemory
Memory that persists during deep sleep. This object is the sole instance of `alarm.SleepMemory`.

**alarm.wake_alarm** :Optional[circuitpython_typing.Alarm]
The most recently triggered alarm. If CircuitPython was sleeping, the alarm that woke it from sleep. If no alarm occurred since the last hard reset or soft restart, value is `None`.

**alarm.light_sleep_until_alarms** (*alarms: circuitpython_typing.Alarm*) → circuitpython_typing.Alarm
Go into a light sleep until awakened one of the alarms. The alarm causing the wake-up is returned, and is also available as `alarm.wake_alarm`.

If no alarms are specified, return immediately.

If CircuitPython is connected to a host computer, the connection will be maintained, and the microcontroller may not actually go into a light sleep. This allows the user to interrupt an existing program with ctrl-C,
and to edit the files in CIRCUITPY, which would not be possible in true light sleep. Thus, to use light sleep and save significant power, it may be necessary to disconnect from the host.

```python
alarm.exit_and_deep_sleep_until_alarms(*alarms: circuitpython_typing.Alarm, preserve_dios:
    Sequence[digitalio.DigitalInOut] = ()) → None
```

Exit the program and go into a deep sleep, until awakened by one of the alarms. This function does not return. When awakened, the microcontroller will restart and will run `boot.py` and `code.py` from the beginning.

After restart, an alarm equivalent to the one that caused the wake-up will be available as `alarm.wake_alarm`. Its type and/or attributes may not correspond exactly to the original alarm. For time-base alarms, currently, an `alarm.time.TimeAlarm()` is created.

If no alarms are specified, the microcontroller will deep sleep until reset.

**Parameters**

- `alarms (circuitpython_typing.Alarm)` – the alarms that can wake the microcontroller.
- `preserve_dios (Sequence[digitalio.DigitalInOut])` – A sequence of `DigitalInOut` objects whose state should be preserved during deep sleep. If a `DigitalInOut` in the sequence is set to be an output, its current `DigitalInOut.value` (True or False) will be preserved during the deep sleep. If a `DigitalInOut` in the sequence is set to be an input, its current `DigitalInOut.pull` value (DOWN, UP, or None) will be preserved during deep sleep.

Preserving `DigitalInOut` states during deep sleep can be used to ensure that external or on-board devices are powered or unpowered during sleep, among other purposes.

On some microcontrollers, some pins cannot remain in their original state for hardware reasons.

**Limitations:** `preserve_dios` is currently only available on Espressif.

---

**Note:** On Espressif chips, preserving pin settings during deep sleep may consume extra current. On ESP32, this was measured to be 250 uA or more. Consider not preserving pins unless you need to. Measure power consumption carefully both with no pins preserved and with the pins you might want to preserve to achieve the lowest consumption.

---

If CircuitPython is connected to a host computer via USB or BLE the first time a deep sleep is requested, the connection will be maintained and the system will not go into deep sleep. This allows the user to interrupt an existing program with ctrl-C, and to edit the files in CIRCUITPY, which would not be possible in true deep sleep.

If CircuitPython goes into a true deep sleep, and USB or BLE is reconnected, the next deep sleep will still be a true deep sleep. You must do a hard reset or power-cycle to exit a true deep sleep loop.

Here is a skeletal example:

```python
import alarm
import time
import board

print("Waking up")

# Create an alarm for 60 seconds from now, and also a pin alarm.
time_alarm = alarm.time.TimeAlarm(monotonic_time=time.monotonic() + 60)
pin_alarm = alarm.pin.PinAlarm(board.D7, False)
```

(continues on next page)
# Deep sleep until one of the alarm goes off. Then restart the program.

```
alarm.exit_and_deep_sleep_until_alarms(time_alarm, pin_alarm)
```

class `alarm.SleepMemory`  
Store raw bytes in RAM that persists during deep sleep. The class acts as a `bytearray`. If power is lost, the memory contents are lost.

Note that this class can’t be imported and used directly. The sole instance of `SleepMemory` is available at `alarm.sleep_memory`.

**Limitations:** Not supported on RP2040.

**Usage:**

```python
import alarm

alarm.sleep_memory[0] = True  
alarm.sleep_memory[1] = 12
```

Not used. Access the sole instance through `alarm.sleep_memory`.

```
__bool__() → bool
   
sleep_memory is True if its length is greater than zero. This is an easy way to check for its existence.

__len__() → int
   
Return the length. This is used by `len`.

__getitem__(index: slice) → bytearray

__getitem__(index: int) → int
   
Returns the value at the given index.

__setitem__(index: slice, value: circuitpython_typing.ReadableBuffer) → None

__setitem__(index: int, value: int) → None
   
Set the value at the given index.
```

**analogbufio — Analog Buffered IO Hardware Support**

The `analogbufio` module contains classes to provide access to analog-to-digital conversion and digital-to-analog (DAC) for multiple value transfer.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See [*Lifetime and Context Managers*](#lifetime-and-context-managers) for more info.

For example:

```python
import analogbufio
import array
from board import *

length = 5000000
mybuffer = array.array("H", 0x0000 for i in range(length))
adc_in = analogbufio.BufferedIn(GP26, mybuffer, length)
analogbufio.read()
print(*mybuffer)
adc_in.deinit()
```
This example will initialize the device, read and fill `BufferedIn` to mybuffer.

TODO: For the essentials of `analogbufio`, see the CircuitPython Essentials Learn guide.

TODO: For more information on using `analogbufio`, see this additional Learn guide.


Capture multiple analog voltage levels to the supplied buffer.

Usage:

```python
import board
import analogbufio
import array

length = 1000
mybuffer = array.array("H", 0x0000 for i in range(length))
rate = 500000
adcbuf = analogbufio.BufferedIn(board.GP26, mybuffer, rate)
adcbuf.read()
adcbuf.deinit()
for i in range(length):
    print(i, mybuffer[i])
```

(TODO) The reference voltage varies by platform so use `reference_voltge` to read the configured setting.

(TODO) Provide mechanism to read CPU Temperature.

Create a `BufferedIn` on the given pin. ADC values will be read into the given buffer at the supplied sample_rate. Depending on the buffer typecode, ‘b’, ‘B’, ‘h’, ‘H’, samples are 8-bit byte-arrays or 16-bit half-words and are signed or unsigned. The ADC most significant bits of the ADC are kept. (See https://docs.circuitpython.org/en/latest/docs/library/array.html)

Parameters

- `pin (Pin)` – the pin to read from
- `buffer (WriteableBuffer)` – buffer: A buffer for samples
- `sample_rate (~int)` – rate: sampling frequency, in samples per second

`deinit()` → None

Shut down the `BufferedIn` and release the pin for other use.

`__enter__()` → `BufferedIn`

No-op used by Context Managers.

`__exit__()` → None

Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

`read()` → None

Fills the provided buffer with ADC voltage values.
analogio – Analog hardware support

The analogio module contains classes to provide access to analog IO typically implemented with digital-to-analog (DAC) and analog-to-digital (ADC) converters.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call deinit() or use a context manager. See Lifetime and ContextManagers for more info.

For example:

```python
import analogio
from board import *

pin = analogio.AnalogIn(A0)
print(pin.value)
pin.deinit()
```

This example will initialize the device, read value and then deinit() the hardware. The last step is optional because CircuitPython will do it automatically after the program finishes.

For the essentials of analogio, see the CircuitPython Essentials Learn guide

For more information on using analogio, see this additional Learn guide

class analogio.AnalogIn(pin: microcontroller.Pin)

Read analog voltage levels

Usage:

```python
import analogio
from board import *

adc = analogio.AnalogIn(A1)
val = adc.value
```

Use the AnalogIn on the given pin. The reference voltage varies by platform so use reference_voltage to read the configured setting.

**Parameters**

- **pin (Pin)** – the pin to read from

- **value :int**
  
The value on the analog pin between 0 and 65535 inclusive (16-bit). (read-only)
  
  Even if the underlying analog to digital converter (ADC) is lower resolution, the value is 16-bit.

- **reference_voltage :float**
  
The maximum voltage measurable (also known as the reference voltage) as a float in Volts. Note the ADC value may not scale to the actual voltage linearly at ends of the analog range.

- **deinit() → None**
  
  Turn off the AnalogIn and release the pin for other use.

- **__enter__() → AnalogIn**
  
  No-op used by Context Managers.

- **__exit__() → None**
  
  Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.
class analogio.AnalogOut(pin: microcontroller.Pin)
Output analog values (a specific voltage).

Limitations: Not available on nRF, RP2040, Spresense, as there is no on-chip DAC. On Espressif, available only on ESP32 and ESP32-S2; other chips do not have a DAC.

Example usage:

```python
import analogio
from board import *
dac = analogio.AnalogOut(A2)  # output on pin A2
dac.value = 32768  # makes A2 1.65V
```

Use the AnalogOut on the given pin.

Parameters

- **pin (Pin)** – the pin to output to

**value :int**
The value on the analog pin between 0 and 65535 inclusive (16-bit). (write-only)

Even if the underlying digital to analog converter (DAC) is lower resolution, the value is 16-bit.

**deinit() → None**
Turn off the AnalogOut and release the pin for other use.

**__enter__() → AnalogOut**
No-op used by Context Managers.

**__exit__() → None**
Automatically deinitializes the hardware when exiting a context. See [Lifetime and Context Managers](#) for more info.

**atexit – Atexit Module**

This module defines functions to register and unregister cleanup functions. Functions thus registered are automatically executed upon normal vm termination.

These functions are run in the reverse order in which they were registered; if you register A, B, and C, they will be run in the order C, B, A.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: [atexit](https://docs.python.org/3/library/atexit.html).

**atexit.register(func: Callable[Ellipsis, Any], *args: Optional[Any], **kwargs: Optional[Any]) → Callable[Ellipsis, Any]**
Register func as a function to be executed at termination.

Any optional arguments that are to be passed to func must be passed as arguments to register(). It is possible to register the same function and arguments more than once.

At normal program termination (for instance, if `sys.exit()` is called or the vm execution completes), all func-
tions registered are called in last in, first out order.

If an exception is raised during execution of the exit handler, a traceback is printed (unless `SystemExit` is raised) and the execution stops.

This function returns func, which makes it possible to use it as a decorator.
atexit.unregister(func: Callable[Ellipsis, Any]) → None
Remove func from the list of functions to be run at termination.

 unregister() silently does nothing if func was not previously registered. If func has been registered more than once, every occurrence of that function in the atexit call stack will be removed.

 audiobusio – Support for audio input and output over digital buses

The audiobusio module contains classes to provide access to audio IO over digital buses. These protocols are used to communicate audio to other chips in the same circuit. It doesn’t include audio interconnect protocols such as S/PDIF.

All classes change hardware state and should be deinitialized when they are no longer needed. To do so, either call deinit() or use a context manager.


Output an I2S audio signal

Create a I2SOut object associated with the given pins.

Parameters

• bit_clock (Pin) – The bit clock (or serial clock) pin
• word_select (Pin) – The word select (or left/right clock) pin
• data (Pin) – The data pin
• left_justified (bool) – True when data bits are aligned with the word select clock. False when they are shifted by one to match classic I2S protocol.

Simple 8ksps 440 Hz sine wave on Metro M0 Express using UDA1334 Breakout:

```python
import audiobusio
import audiocore
import board
import array
import time
import math

# Generate one period of sine wave.
length = 8000 // 440
sine_wave = array.array("H", [0] * length)
for i in range(length):
    sine_wave[i] = int(math.sin(math.pi * 2 * i / length) * (2 ** 15) + 2 ** 15)
sine_wave = audiocore.RawSample(sine_wave, sample_rate=8000)
i2s = audiobusio.I2SOut(board.D1, board.D0, board.D9)
i2s.play(sine_wave, loop=True)
time.sleep(1)
i2s.stop()
```

Playing a wave file from flash:

```python
import board
import audiocore
import audiobusio
```
import digitalio

f = open("cplay-5.1-16bit-16khz.wav", "rb")
wav = audiocore.WaveFile(f)

a = audiobusio.I2SOut(board.D1, board.D0, board.D9)

print("playing")
a.play(wav)
while a.playing:
    pass
print("stopped")

playing :bool
    True when the audio sample is being output. (read-only)

paused :bool
    True when playback is paused. (read-only)

definit() → None
    Deinitialises the I2SOut and releases any hardware resources for reuse.

__enter__() → I2SOut
    No-op used by Context Managers.

__exit__() → None
    Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

play(sample: circuitpython_typing.AudioSample, *, loop: bool = False) → None
    Plays the sample once when loop=False and continuously when loop=True. Does not block. Use playing to block.

    Sample must be an audiocore.WaveFile, audiocore.RawSample, audiomixer.Mixer or audiomp3.MP3Decoder.

    The sample itself should consist of 8 bit or 16 bit samples.

stop() → None
    Stops playback.

pause() → None
    Stops playback temporarily while remembering the position. Use resume to resume playback.

resume() → None
    Resumes sample playback after pause().

class audiobusio.PDMIn(clock_pin: microcontroller.Pin, data_pin: microcontroller.Pin, *, sample_rate: int = 16000, bit_depth: int = 8, mono: bool = True, oversample: int = 64, startup_delay: float = 0.11)

    Record an input PDM audio stream

    Create a PDMIn object associated with the given pins. This allows you to record audio signals from the given pins. Individual ports may put further restrictions on the recording parameters. The overall sample rate is determined by sample_rate x oversample, and the total must be 1MHz or higher, so sample_rate must be a minimum of 16000.
Parameters

- **clock_pin** *(Pin)* – The pin to output the clock to
- **data_pin** *(Pin)* – The pin to read the data from
- **sample_rate** *(int)* – Target sample_rate of the resulting samples. Check `sample_rate` for actual value. Minimum sample_rate is about 16000 Hz.
- **bit_depth** *(int)* – Final number of bits per sample. Must be divisible by 8
- **mono** *(bool)* – True when capturing a single channel of audio, captures two channels otherwise
- **oversample** *(int)* – Number of single bit samples to decimate into a final sample. Must be divisible by 8
- **startup_delay** *(float)* – seconds to wait after starting microphone clock to allow microphone to turn on. Most require only 0.01s; some require 0.1s. Longer is safer. Must be in range 0.0-1.0 seconds.

Limitations: On SAMD and RP2040, supports only 8 or 16 bit mono input, with 64x oversampling. On nRF52840, supports only 16 bit mono input at 16kHz; oversampling is fixed at 64x. Not provided on nRF52833 for space reasons. Not available on Espressif.

For example, to record 8-bit unsigned samples to a buffer:

```python
import audiobusio
import board

# Prep a buffer to record into
b = bytearray(200)
with audiobusio.PDMIn(board.MICROPHONE_CLOCK, board.MICROPHONE_DATA, sample_rate=16000) as mic:
    mic.record(b, len(b))
```

To record 16-bit unsigned samples to a buffer:

```python
import audiobusio
import board

# Prep a buffer to record into.
B = array.array("H", [0] * 200)
with audiobusio.PDMIn(board.MICROPHONE_CLOCK, board.MICROPHONE_DATA, sample_rate=16000, bit_depth=16) as mic:
    mic.record(B, len(B))
```

**sample_rate**: int

The actual sample_rate of the recording. This may not match the constructed sample rate due to internal clock limitations.

**deinit** → None

Deinitialises the PDMIn and releases any hardware resources for reuse.

**__enter__** → *PDMIn*

No-op used by Context Managers.

**__exit__** → None

Automatically deinitializes the hardware when exiting a context.
**record** *(destination: circuitpython_typing.WriteableBuffer, destination_length: int) → None*

Records `destination_length` bytes of samples to `destination`. This is blocking.

An `IOError` may be raised when the destination is too slow to record the audio at the given rate. For internal flash, writing all 1s to the file before recording is recommended to speed up writes.

**Returns**

The number of samples recorded. If this is less than `destination_length`, some samples were missed due to processing time.

---

**audiocore** – Support for audio samples

**class audiocore.RawSample**(buffer: circuitpython_typing.ReadableBuffer, *, channel_count: int = 1, sample_rate: int = 8000)

A raw audio sample buffer in memory

Create a `RawSample` based on the given buffer of signed values. If `channel_count` is more than 1 then each channel's samples should alternate. In other words, for a two channel buffer, the first sample will be for channel 1, the second sample will be for channel two, the third for channel 1 and so on.

**Parameters**

- **buffer** *(ReadableBuffer)* – A buffer with samples
- **channel_count** *(int)* – The number of channels in the buffer
- **sample_rate** *(int)* – The desired playback sample rate

Simple 8ksps 440 Hz sin wave:

```python
import audiocore
import audioio
import board
import array
import time
import math

# Generate one period of sine wav.
length = 8000 // 440
sine_wave = array.array("h", [0] * length)
for i in range(length):
    sine_wave[i] = int(math.sin(math.pi * 2 * i / length) * (2 ** 15))

dac = audioio.AudioOut(board.SPEAKER)
sine_wave = audiocore.RawSample(sine_wave)
dac.play(sine_wave, loop=True)
time.sleep(1)
dac.stop()```

**sample_rate**:Optional[int]

32 bit value that dictates how quickly samples are played in Hertz (cycles per second). When the sample is looped, this can change the pitch output without changing the underlying sample. This will not change the sample rate of any active playback. Call `play` again to change it.

**deinit** *(→ None)*

Deinitialises the `RawSample` and releases any hardware resources for reuse.
__enter__(\() \rightarrow \texttt{RawSample} \\
\text{No-op used by Context Managers.} \\
__exit__(\()) \rightarrow \texttt{None} \\
\text{Automatically deinitializes the hardware when exiting a context. See \textit{Lifetime and ContextManagers} for more info.}

class \texttt{audiocore.WaveFile}(\texttt{file: Union[str, BinaryIO]}, \texttt{buffer: circuitpython\textunderscore\texttt{typing}.WriteableBuffer}) \\
\text{Load a wave file for audio playback} \\
\text{A.wav file prepped for audio playback. Only mono and stereo files are supported. Samples must be 8 bit unsigned or 16 bit signed. If a buffer is provided, it will be used instead of allocating an internal buffer, which can prevent memory fragmentation.} \\
\text{Load a .wav file for playback with \textit{audioio.AudioOut} or \textit{audiobusio.I2SOut}.} \\
\textbf{Parameters} \\
\begin{itemize} \\
\item \texttt{file}(\texttt{Union[str, BinaryIO]}) – The name of a wave file (preferred) or an already opened wave file \\
\item \texttt{buffer}(\texttt{WriteableBuffer}) – Optional pre-allocated buffer, that will be split in half and used for double-buffering of the data. The buffer must be 8 to 1024 bytes long. If not provided, two 256 byte buffers are initially allocated internally. \\
\end{itemize} \\
\textbf{Playing a wave file from flash:} \\
\begin{verbatim} 
import board 
import audiocore 
import audioio 
import digitalio 

# Required for CircuitPlayground Express 
speaker_enable = digitalio.DigitalInOut(board.SPEAKER_ENABLE) 
speaker_enable.switch_to_output(value=True) 

wav = audiocore.WaveFile("cplay-5.1-16bit-16khz.wav") 
a = audioio.AudioOut(board.A0) 

print("playing") 
a.play(wav) 
while a.playing: 
    pass 
print("stopped") 
\end{verbatim} 

\textbf{sample_rate :int} \\
\text{32 bit value that dictates how quickly samples are loaded into the DAC in Hertz (cycles per second). When the sample is looped, this can change the pitch output without changing the underlying sample.} 

\textbf{bits_per_sample :int} \\
\text{Bits per sample. (read only)} 

\textbf{channel_count :int} \\
\text{Number of audio channels. (read only)} 

\textbf{deinit() \rightarrow None} \\
\text{Deinitialises the WaveFile and releases all memory resources for reuse.}
__enter__() → WaveFile
  No-op used by Context Managers.

__exit__() → None
  Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

**audioio** – Support for audio output

The *audioio* module contains classes to provide access to audio IO.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call deinit() or use a context manager. See *Lifetime and ContextManagers* for more info.

For more information on working with this module, refer to the CircuitPython Essentials Learn Guide.

Since CircuitPython 5, *RawSample* and *WaveFile* are moved to *audiocore*, and *Mixer* is moved to *audiomixer*.

For compatibility with CircuitPython 4.x, some builds allow the items in *audiocore* to be imported from *audioio*. This will be removed for all boards in a future build of CircuitPython.

```python
  Output an analog audio signal

Create a AudioOut object associated with the given pin(s). This allows you to play audio signals out on the given pin(s).

Parameters
  • **left_channel** (Pin) – The pin to output the left channel to
  • **right_channel** (Pin) – The pin to output the right channel to
  • **quiescent_value** (int) – The output value when no signal is present. Samples should start and end with this value to prevent audible popping.

Simple 8ksps 440 Hz sin wave:

```python
import audiocore
import audioio
import board
import array
import time
import math

# Generate one period of sine wav.
length = 8000 // 440
sine_wave = array.array("H", [0] * length)
for i in range(length):
    sine_wave[i] = int(math.sin(math.pi * 2 * i / length) * (2 ** 15) + 2 ** 15)

dac = audioio.AudioOut(board.SPEAKER)
sine_wave = audiocore.RawSample(sine_wave, sample_rate=8000)
dac.play(sine_wave, loop=True)
time.sleep(1)
dac.stop()
```
Playing a wave file from flash:

```python
import board
import audioio
import digitalio

# Required for CircuitPlayground Express
speaker_enable = digitalio.DigitalInOut(board.SPEAKER_ENABLE)
speaker_enable.switch_to_output(value=True)

data = open("cplay-5.1-16bit-16khz.wav", "rb")
wav = audiocore.WaveFile(data)
a = audioio.AudioOut(board.A0)

print("playing")
a.play(wav)
while a.playing:
    pass
print("stopped")
```

`playing :bool`
- True when an audio sample is being output even if `paused`. (read-only)

`paused :bool`
- True when playback is paused. (read-only)

`deinit`() → None
- Deinitialises the AudioOut and releases any hardware resources for reuse.

`__enter__`() → `AudioOut`
- No-op used by Context Managers.

`__exit__`() → None
- Automatically deinitializes the hardware when exiting a context. See `Lifetime and ContextManagers` for more info.

`play`(sample: `circuitpython_typing.AudioSample`, *, loop: `bool = False`) → `None`
- Plays the sample once when loop=False and continuously when loop=True. Does not block. Use `playing` to block.

- Sample must be an `audiocore.WaveFile`, `audiocore.RawSample`, `audiomixer.Mixer` or `audiomp3.MP3Decoder`.

- The sample itself should consist of 16 bit samples. Microcontrollers with a lower output resolution will use the highest order bits to output. For example, the SAMD21 has a 10 bit DAC that ignores the lowest 6 bits when playing 16 bit samples.

`stop`() → None
- Stops playback and resets to the start of the sample.

`pause`() → None
- Stops playback temporarily while remembering the position. Use `resume` to resume playback.

`resume`() → None
- Resumes sample playback after `pause()`.
audiomixer – Support for audio mixing

class audiomixer.Mixer(voice_count: int = 2, buffer_size: int = 1024, channel_count: int = 2, bits_per_sample: int = 16, samples_signed: bool = True, sample_rate: int = 8000)

Mixes one or more audio samples together into one sample.

Create a Mixer object that can mix multiple channels with the same sample rate. Samples are accessed and controlled with the mixer’s audiomixer.MixerVoice objects.

Parameters

• voice_count (int) – The maximum number of voices to mix
• buffer_size (int) – The total size in bytes of the buffers to mix into
• channel_count (int) – The number of channels the source samples contain. 1 = mono; 2 = stereo.
• bits_per_sample (int) – The bits per sample of the samples being played
• samples_signed (bool) – Samples are signed (True) or unsigned (False)
• sample_rate (int) – The sample rate to be used for all samples

Playing a wave file from flash:

```python
import board
import audioio
import audiocore
import audiomixer
import digitalio

a = audioio.AudioOut(board.A0)
music = audiocore.WaveFile(open("cplay-5.1-16bit-16khz.wav", "rb"))
drum = audiocore.WaveFile(open("drum.wav", "rb"))
mixer = audiomixer.Mixer(voice_count=2, sample_rate=16000, channel_count=1, bits_per_sample=16, samples_signed=True)

print("playing")
# Have AudioOut play our Mixer source
a.play(mixer)
# Play the first sample voice
mixer.voice[0].play(music)
while mixer.playing:
    # Play the second sample voice
    mixer.voice[1].play(drum)
    time.sleep(1)
print("stopped")
```

playing :bool
True when any voice is being output. (read-only)

sample_rate :int
32 bit value that dictates how quickly samples are played in Hertz (cycles per second).

voice :Tuple[MixerVoice, Ellipsis]
A tuple of the mixer’s audiomixer.MixerVoice object(s).
```python
>>> mixer.voice
(<MixerVoice>,)
```

**deinit() → None**

Deinitialises the Mixer and releases any hardware resources for reuse.

**__enter__() → Mixer**

No-op used by Context Managers.

**__exit__() → None**

Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

**play(sample: circuitpython_typing.AudioSample, *, voice: int = 0, loop: bool = False) → None**

Plays the sample once when loop=False and continuously when loop=True. Does not block. Use *playing* to block.

Sample must be an *audiocore.WaveFile, audiocore.RawSample, audiomixer.Mixer* or *audiomp3.MP3Decoder*.

The sample must match the Mixer's encoding settings given in the constructor.

**stop_voice(voice: int = 0) → None**

Stops playback of the sample on the given voice.

```python
class audiomixer.MixerVoice
```

Voice objects used with Mixer

Used to access and control samples with *audiomixer.Mixer*.

MixerVoice instance object(s) created by *audiomixer.Mixer*.

**level : float**

The volume level of a voice, as a floating point number between 0 and 1.

**playing : bool**

True when this voice is being output. (read-only)

**play(sample: circuitpython_typing.AudioSample, *, loop: bool = False) → None**

Plays the sample once when loop=False, and continuously when loop=True. Does not block. Use *playing* to block.

Sample must be an *audiocore.WaveFile, audiocore.RawSample, audiomixer.Mixer* or *audiomp3.MP3Decoder*.

The sample must match the *audiomixer.Mixer*'s encoding settings given in the constructor.

**stop() → None**

Stops playback of the sample on this voice.
### audiomp3 – Support for MP3-compressed audio files

For more information about working with MP3 files in CircuitPython, see the CircuitPython Essentials Learn guide page.

```python
class audiomp3.MP3Decoder(file: Union[str, BinaryIO], buffer: circuitpython_typing.WriteableBuffer)
```

Load a mp3 file for audio playback

**Note:** MP3Decoder uses a lot of contiguous memory, so care should be given to optimizing memory usage. More information and recommendations can be found here: [https://learn.adafruit.com/Memory-saving-tips-for-CircuitPython/reducing-memory-fragmentation](https://learn.adafruit.com/Memory-saving-tips-for-CircuitPython/reducing-memory-fragmentation)

Load a .mp3 file for playback with `audioio.AudioOut` or `audiobusio.I2SOut`.

**Parameters**

- `file` *(Union[str, BinaryIO])* – The name of a mp3 file (preferred) or an already opened mp3 file
- `buffer` *(WriteableBuffer)* – Optional pre-allocated buffer, that will be split in half and used for double-buffering of the data. If not provided, two buffers are allocated internally. The specific buffer size required depends on the mp3 file.

Playback of mp3 audio is CPU intensive, and the exact limit depends on many factors such as the particular microcontroller, SD card or flash performance, and other code in use such as displayio. If playback is garbled, skips, or plays as static, first try using a “simpler” mp3:

- Use constant bit rate (CBR) not VBR or ABR (variable or average bit rate) when encoding your mp3 file
- Use a lower sample rate (e.g., 11.025kHz instead of 48kHz)
- Use a lower bit rate (e.g., 32kbit/s instead of 256kbit/s)

Reduce activity taking place at the same time as mp3 playback. For instance, only update small portions of a displayio screen if audio is playing. Disable auto-refresh and explicitly call refresh.

Playing a mp3 file from flash:

```python
import board
import audiomp3
import audioio
import digitalio

# Required for CircuitPlayground Express
speaker_enable = digitalio.DigitalInOut(board.SPEAKER_ENABLE)
speaker_enable.switch_to_output(value=True)

mp3 = audiomp3.MP3Decoder("cplay-16bit-16khz-64kbps.mp3")
a = audioio.AudioOut(board.A0)

print("playing")
a.play(mp3)
while a.playing:
    pass
print("stopped")
```
file : BinaryIO
File to play back.

**sample_rate : int**
32 bit value that dictates how quickly samples are loaded into the DAC in Hertz (cycles per second). When the sample is looped, this can change the pitch output without changing the underlying sample.

**bits_per_sample : int**
Bits per sample. (read only)

**channel_count : int**
Number of audio channels. (read only)

**rms_level : float**
The RMS audio level of a recently played moment of audio. (read only)

**samples_decoded : int**
The number of audio samples decoded from the current file. (read only)

**deinit() → None**
Deinitialises the MP3 and releases all memory resources for reuse.

**__enter__() → MP3Decoder**
No-op used by Context Managers.

**__exit__() → None**
Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

**open(filepath: str) → None**
Takes in the name of a mp3 file, opens it, and replaces the old playback file.

---

**audiopwmio – Audio output via digital PWM**

The *audiopwmio* module contains classes to provide access to audio IO.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call *deinit()* or use a context manager. See *Lifetime and ContextManagers* for more info.

Since CircuitPython 5, *Mixer, RawSample* and *WaveFile* are moved to *audiocore*.

**class audiopwmio.PWMAudioOut(left_channel: microcontroller.Pin, *, right_channel: Optional[microcontroller.Pin] = None, quiescent_value: int = 32768)**

Output an analog audio signal by varying the PWM duty cycle.

Create a *PWMAudioOut* object associated with the given pin(s). This allows you to play audio signals out on the given pin(s). In contrast to mod:*audioio*, the pin(s) specified are digital pins, and are driven with a device-dependent PWM signal.

**Parameters**

- **left_channel (Pin)** – The pin to output the left channel to
- **right_channel (Pin)** – The pin to output the right channel to
- **quiescent_value (int)** – The output value when no signal is present. Samples should start and end with this value to prevent audible popping.

Simple 8ksps 440 Hz sin wave:
```python
import audiocore
import audiopwmio
import board
import array
import time
import math

# Generate one period of sine wav.
length = 8000 // 440
sine_wave = array.array("H", [0] * length)
for i in range(length):
    sine_wave[i] = int(math.sin(math.pi * 2 * i / length) * (2 ** 15) + 2 ** 15)

dac = audiopwmio.PWMAudioOut(board.SPEAKER)
sine_wave = audiocore.RawSample(sine_wave, sample_rate=8000)
dac.play(sine_wave, loop=True)
time.sleep(1)
dac.stop()
```

Playing a wave file from flash:

```python
import board
import audiocore
import audiopwmio
import digitalio

# Required for CircuitPlayground Express
speaker_enable = digitalio.DigitalInOut(board.SPEAKER_ENABLE)
speaker_enable.switch_to_output(value=True)

data = open("cplay-5.1-16bit-16khz.wav", "rb")
wav = audiocore.WaveFile(data)
a = audiopwmio.PWMAudioOut(board.SPEAKER)

print("playing")
a.play(wav)
while a.playing:
    pass
print("stopped")
```

```
playing :bool
    True when an audio sample is being output even if paused. (read-only)

paused :bool
    True when playback is paused. (read-only)

deinit() → None
    Deinitialises the PWMAudioOut and releases any hardware resources for reuse.

__enter__() → PWMAudioOut
    No-op used by Context Managers.

__exit__() → None
    Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.
```
play(sample: circuitpython_typing.AudioSample, *, loop: bool = False) → None

Plays the sample once when loop=False and continuously when loop=True. Does not block. Use playing to block.

Sample must be an audiocore.WaveFile, audiocore.RawSample, audiomixer.Mixer or audiomp3.MP3Decoder.

The sample itself should consist of 16 bit samples. Microcontrollers with a lower output resolution will use the highest order bits to output.

stop() → None

Stops playback and resets to the start of the sample.

pause() → None

Stops playback temporarily while remembering the position. Use resume to resume playback.

resume() → None

Resumes sample playback after pause().

bitbangio – Digital protocols implemented by the CPU

The bitbangio module contains classes to provide digital bus protocol support regardless of whether the underlying hardware exists to use the protocol.

First try to use busio module instead which may utilize peripheral hardware to implement the protocols. Native implementations will be faster than bitbanged versions and have more capabilities.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call deinit() or use a context manager. See Lifetime and ContextManagers for more info.

For example:

```python
import bitbangio
from board import *

i2c = bitbangio.I2C(SCL, SDA)
print(i2c.scan())
i2c.deinit()
```

This example will initialize the the device, run scan() and then deinit() the hardware. The last step is optional because CircuitPython automatically resets hardware after a program finishes.


Two wire serial protocol

I2C is a two-wire protocol for communicating between devices. At the physical level it consists of 2 wires: SCL and SDA, the clock and data lines respectively.

See also:

Using this class directly requires careful lock management. Instead, use I2CDevice to manage locks.

See also:

Using this class to directly read registers requires manual bit unpacking. Instead, use an existing driver or make one with Register data descriptors.

Parameters
- **scl (Pin)** – The clock pin
- **sda (Pin)** – The data pin
- **frequency (int)** – The clock frequency of the bus
- **timeout (int)** – The maximum clock stretching timeout in microseconds

**deinit() → None**
Releases control of the underlying hardware so other classes can use it.

**__enter__() → I2C**
No-op used in Context Managers.

**__exit__() → None**
Automatically deinitializes the hardware on context exit. See *Lifetime and ContextManagers* for more info.

**scan() → List[int]**
Scan all I2C addresses between 0x08 and 0x77 inclusive and return a list of those that respond. A device responds if it pulls the SDA line low after its address (including a read bit) is sent on the bus.

**try_lock() → bool**
Attempts to grab the I2C lock. Returns True on success.

**unlock() → None**
Releases the I2C lock.

**readfrom_into(address: int, buffer: circuitpython_typing.WriteableBuffer, *, start: int = 0, end: int = sys.maxsize) → None**
Read into buffer from the device selected by address. The number of bytes read will be the length of buffer. At least one byte must be read.

If start or end is provided, then the buffer will be sliced as if buffer[start:end]. This will not cause an allocation like buf[start:end] will so it saves memory.

**Parameters**

- **address (int)** – 7-bit device address
- **buffer (WriteableBuffer)** – buffer to write into
- **start (int)** – Index to start writing at
- **end (int)** – Index to write up to but not include

**writeto(address: int, buffer: circuitpython_typing.ReadableBuffer, *, start: int = 0, end: int = int = sys.maxsize) → None**
Write the bytes from buffer to the device selected by address and then transmits a stop bit. Use **writeto_then_readfrom when needing a write, no stop and repeated start before a read.**

If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed, but without copying the data. The number of bytes written will be the length of buffer[start:end].

Writing a buffer or slice of length zero is permitted, as it can be used to poll for the existence of a device.

**Parameters**

- **address (int)** – 7-bit device address
- **buffer (ReadableBuffer)** – buffer containing the bytes to write
- **start (int)** – beginning of buffer slice
• **end** (*int*) – end of buffer slice; if not specified, use `len(buffer)`

`writeto_then_readfrom`(*address: int, out_buffer: circuitpython_typing.ReadableBuffer, in_buffer: circuitpython_typing.ReadableBuffer, *, out_start: int = 0, out_end: int = sys.maxsize, in_start: int = 0, in_end: int = sys.maxsize*) → None

Write the bytes from `out_buffer` to the device selected by `address`, generate no stop bit, generate a repeated start and read into `in_buffer`. `out_buffer` and `in_buffer` can be the same buffer because they are used sequentially.

If `out_start` or `out_end` is provided, then the buffer will be sliced as if `out_buffer[out_start:out_end]` were passed, but without copying the data. The number of bytes written will be the length of `out_buffer[start:end]`.

If `in_start` or `in_end` is provided, then the input buffer will be sliced as if `in_buffer[in_start:in_end]` were passed. The number of bytes read will be the length of `out_buffer[in_start:in_end]`.

**Parameters**

- **address** (*int*) – 7-bit device address
- **out_buffer** (*ReadableBuffer*) – buffer containing the bytes to write
- **in_buffer** (*WriteableBuffer*) – buffer to write into
- **out_start** (*int*) – beginning of `out_buffer` slice
- **out_end** (*int*) – end of `out_buffer` slice; if not specified, use `len(out_buffer)`
- **in_start** (*int*) – beginning of `in_buffer` slice
- **in_end** (*int*) – end of `in_buffer` slice; if not specified, use `len(in_buffer)`

```python
```

A 3-4 wire serial protocol

SPI is a serial protocol that has exclusive pins for data in and out of the main device. It is typically faster than **I2C** because a separate pin is used to select a device rather than a transmitted address. This class only manages three of the four SPI lines: `clock`, `MOSI`, `MISO`. It’s up to the client to manage the appropriate select line, often abbreviated CS or SS. (This is common because multiple secondaries can share the `clock`, `MOSI` and `MISO` lines and therefore the hardware.)

Construct an SPI object on the given pins.

**See also:**

Using this class directly requires careful lock management. Instead, use `SPIDevice` to manage locks.

**See also:**

Using this class to directly read registers requires manual bit unpacking. Instead, use an existing driver or make one with `Register` data descriptors.

**Parameters**

- **clock** (*Pin*) – the pin to use for the clock.
- **MOSI** (*Pin*) – the Main Out Selected In pin.
- **MISO** (*Pin*) – the Main In Selected Out pin.
deinit() → None
Turn off the SPI bus.
__enter__( ) → SPI
No-op used by Context Managers.
__exit__( ) → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

configure(*, baudrate: int = 100000, polarity: int = 0, phase: int = 0, bits: int = 8) → None
Configures the SPI bus. Only valid when locked.

Parameters
• baudrate (int) – the clock rate in Hertz
• polarity (int) – the base state of the clock line (0 or 1)
• phase (int) – the edge of the clock that data is captured. First (0) or second (1). Rising or falling depends on clock polarity.
• bits (int) – the number of bits per word

try_lock() → bool
Attempts to grab the SPI lock. Returns True on success.

Returns
True when lock has been grabbed

Return type
bool

unlock() → None
Releases the SPI lock.

write(buf: circuitpython_typing.ReadableBuffer) → None
Write the data contained in buf. Requires the SPI being locked. If the buffer is empty, nothing happens.

readinto(buffer: circuitpython_typing.WriteableBuffer, *, start: int = 0, end: int = sys.maxsize, write_value: int = 0) → None
Read into buffer while writing write_value for each byte read. The SPI object must be locked. If the number of bytes to read is 0, nothing happens.

If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed. The number of bytes read will be the length of buffer[start:end].

Parameters
• buffer (WriteableBuffer) – read bytes into this buffer
• start (int) – beginning of buffer slice
• end (int) – end of buffer slice; if not specified, use len(buffer)
• write_value (int) – value to write while reading

write_readinto(out_buffer: circuitpython_typing.ReadableBuffer, in_buffer: circuitpython_typing.WriteableBuffer, *, out_start: int = 0, out_end: int = sys.maxsize, in_start: int = 0, in_end: int = sys.maxsize) → None
Write out the data in out_buffer while simultaneously reading data into in_buffer. The SPI object must be locked.
If `out_start` or `out_end` is provided, then the buffer will be sliced as if `out_buffer[out_start:out_end]` were passed, but without copying the data. The number of bytes written will be the length of `out_buffer[out_start:out_end]`.

If `in_start` or `in_end` is provided, then the input buffer will be sliced as if `in_buffer[in_start:in_end]` were passed. The number of bytes read will be the length of `in_buffer[in_start:in_end]`.

The lengths of the slices defined by `out_buffer[out_start:out_end]` and `in_buffer[in_start:in_end]` must be equal. If buffer slice lengths are both 0, nothing happens.

**Parameters**

- `out_buffer` ([ReadableBuffer](https://micropython-docs.readthedocs.io/en/latest/api/core/ReadableBuffer.html)) – write out bytes from this buffer
- `in_buffer` ([WriteableBuffer](https://micropython-docs.readthedocs.io/en/latest/api/core/WriteableBuffer.html)) – read bytes into this buffer
- `out_start` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – beginning of `out_buffer` slice
- `out_end` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – end of `out_buffer` slice; if not specified, use `len(out_buffer)`
- `in_start` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – beginning of `in_buffer` slice
- `in_end` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – end of `in_buffer` slice; if not specified, use `len(in_buffer)`

**bitmaptools** – Collection of bitmap manipulation tools

**Note:** If you're looking for information about displaying bitmaps on screens in CircuitPython, see this [Learn guide](https://learn.adafruit.com/) for information about using the `displayio` module.

```python
bitmaptools.rotozoom(dest_bitmap: displayio.Bitmap, source_bitmap: displayio.Bitmap, *, ox: int, oy: int,
                     dest_clip0: Tuple[int, int], dest_clip1: Tuple[int, int], px: int, py: int,
                     source_clip0: Tuple[int, int], source_clip1: Tuple[int, int], angle: float,
                     scale: float, skip_index: int) → None
```

Inserts the source bitmap region into the destination bitmap with rotation (angle), scale and clipping (both on source and destination bitmaps).

**Parameters**

- `dest_bitmap` ([bitmap](https://micropython-docs.readthedocs.io/en/latest/api/core/bitmap.html)) – Destination bitmap that will be copied into
- `source_bitmap` ([bitmap](https://micropython-docs.readthedocs.io/en/latest/api/core/bitmap.html)) – Source bitmap that contains the graphical region to be copied
- `ox` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – Horizontal pixel location in destination bitmap where source bitmap point (px,py) is placed. Defaults to None which causes it to use the horizontal midway point of the destination bitmap.
- `oy` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – Vertical pixel location in destination bitmap where source bitmap point (px,py) is placed. Defaults to None which causes it to use the vertical midway point of the destination bitmap.
- `dest_clip0` ([Tuple[int, int]](https://micropython-docs.readthedocs.io/en/latest/api/core/Tuple.html)) – First corner of rectangular destination clipping region that constrains region of writing into destination bitmap
- `dest_clip1` ([Tuple[int, int]](https://micropython-docs.readthedocs.io/en/latest/api/core/Tuple.html)) – Second corner of rectangular destination clipping region that constrains region of writing into destination bitmap
- `px` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – Horizontal pixel location in source bitmap that is placed into the destination bitmap at (ox,oy). Defaults to None which causes it to use the horizontal midway point in the source bitmap.
- `py` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – Vertical pixel location in source bitmap that is placed into the destination bitmap at (ox,oy). Defaults to None which causes it to use the vertical midway point in the source bitmap.
- `angle` ([float](https://micropython-docs.readthedocs.io/en/latest/api/core/float.html)) – The angle of rotation to apply to the source bitmap. Defaults to 0.
- `scale` ([float](https://micropython-docs.readthedocs.io/en/latest/api/core/float.html)) – The scale factor to apply to the source bitmap. Defaults to 1.
- `skip_index` ([int](https://micropython-docs.readthedocs.io/en/latest/api/core/int.html)) – The index of the pixel to be skipped when copying the source bitmap into the destination bitmap. Defaults to 0.
• **py** (*int*) – Vertical pixel location in source bitmap that is placed into the destination bitmap at (ox,oy). Defaults to None which causes it to use the vertical midway point in the source bitmap.

• **source_clip0** (*Tuple*[int, int]*) – First corner of rectangular source clipping region that constrains region of reading from the source bitmap

• **source_clip1** (*Tuple*[int, int]*) – Second corner of rectangular source clipping region that constrains region of reading from the source bitmap

• **angle** (*float*) – Angle of rotation, in radians (positive is clockwise direction). Defaults to None which gets treated as 0.0 radians or no rotation.

• **scale** (*float*) – Scaling factor. Defaults to None which gets treated as 1.0 or same as original source size.

• **skip_index** (*int*) – Bitmap palette index in the source that will not be copied, set to None to copy all pixels

```python
```

Alpha blend the two source bitmaps into the destination.

It is permitted for the destination bitmap to be one of the two source bitmaps.

**Parameters**

• **dest_bitmap** (*bitmap*) – Destination bitmap that will be written into

• **source_bitmap_1** (*bitmap*) – The first source bitmap

• **source_bitmap_2** (*bitmap*) – The second source bitmap

• **factor1** (*float*) – The proportion of bitmap 1 to mix in

• **factor2** (*float*) – The proportion of bitmap 2 to mix in. If specified as None, 1-factor1 is used. Usually the proportions should sum to 1.

• **colorspace** (*displayio.Colorspace*) – The colorspace of the bitmaps. They must all have the same colorspace. Only the following colorspaces are permitted: L8, RGB565, RGB565_SWAPPED, BGR565 and BGR565_SWAPPED.

For the L8 colorspace, the bitmaps must have a bits-per-value of 8. For the RGB colorspaces, they must have a bits-per-value of 16.

```python
bitmaptools.fill_region(dest_bitmap: displayio.Bitmap, x1: int, y1: int, x2: int, y2: int, value: int) → None
```

Draws the color value into the destination bitmap within the rectangular region bounded by (x1,y1) and (x2,y2), exclusive.

**Parameters**

• **dest_bitmap** (*bitmap*) – Destination bitmap that will be written into

• **x1** (*int*) – x-pixel position of the first corner of the rectangular fill region

• **y1** (*int*) – y-pixel position of the first corner of the rectangular fill region

• **x2** (*int*) – x-pixel position of the second corner of the rectangular fill region (exclusive)

• **y2** (*int*) – y-pixel position of the second corner of the rectangular fill region (exclusive)

• **value** (*int*) – Bitmap palette index that will be written into the rectangular fill region in the destination bitmap
bitmaptools.

**boundary_fill**(*dest_bitmap: displayio.Bitmap, x: int, y: int, fill_color_value: int, replaced_color_value: int*) → None

Draws the color value into the destination bitmap enclosed area of pixels of the background_value color. Like “Paint Bucket” fill tool.

**Parameters**

- **dest_bitmap** (*bitmap*) – Destination bitmap that will be written into
- **x** (*int*) – x-pixel position of the first pixel to check and fill if needed
- **y** (*int*) – y-pixel position of the first pixel to check and fill if needed
- **fill_color_value** (*int*) – Bitmap palette index that will be written into the enclosed area in the destination bitmap
- **replaced_color_value** (*int*) – Bitmap palette index that will filled with the value color in the enclosed area in the destination bitmap

bitmaptools.

**draw_line**(*dest_bitmap: displayio.Bitmap, x1: int, y1: int, x2: int, y2: int, value: int*) → None

Draws a line into a bitmap specified two endpoints (x1,y1) and (x2,y2).

**Parameters**

- **dest_bitmap** (*bitmap*) – Destination bitmap that will be written into
- **x1** (*int*) – x-pixel position of the line’s first endpoint
- **y1** (*int*) – y-pixel position of the line’s first endpoint
- **x2** (*int*) – x-pixel position of the line’s second endpoint
- **y2** (*int*) – y-pixel position of the line’s second endpoint
- **value** (*int*) – Bitmap palette index that will be written into the line in the destination bitmap

bitmaptools.

**arrayblit**(*bitmap: displayio.Bitmap, data: circuitpython_typing.ReadableBuffer, x1: int = 0, y1: int = 0, x2: int = None, y2: int = None, skip_index: int = None*) → None

Inserts pixels from data into the rectangle of width×height pixels with the upper left corner at (x,y)

The values from data are taken modulo the number of color values avalable in the destination bitmap.

If x1 or y1 are not specified, they are taken as 0. If x2 or y2 are not specified, or are given as -1, they are taken as the width and height of the image.

The coordinates affected by the blit are x1 <= x < x2 and y1 <= y < y2.

data must contain at least as many elements as required. If it contains excess elements, they are ignored.

The blit takes place by rows, so the first elements of data go to the first row, the next elements to the next row, and so on.

**Parameters**

- **bitmap** (*displayio.Bitmap*) – A writable bitmap
- **data** (*ReadableBuffer*) – Buffer containing the source pixel values
- **x1** (*int*) – The left corner of the area to blit into (inclusive)
- **y1** (*int*) – The top corner of the area to blit into (inclusive)
- **x2** (*int*) – The right of the area to blit into (exclusive)
- **y2** (*int*) – The bottom corner of the area to blit into (exclusive)
• **skip_index**(int) – Bitmap palette index in the source that will not be copied, set to None to copy all pixels


Reads from a binary file into a bitmap.

The file must be positioned so that it consists of `bitmap.height` rows of pixel data, where each row is the smallest multiple of `element_size` bytes that can hold `bitmap.width` pixels.

The bytes in an element can be optionally swapped, and the pixels in an element can be reversed. Also, the row loading direction can be reversed, which may be requires for loading certain bitmap files.

This function doesn’t parse image headers, but is useful to speed up loading of uncompressed image formats such as PCF glyph data.

**Parameters**

- **bitmap**(displayio.Bitmap) – A writable bitmap
- **file**(BinaryIO) – A file opened in binary mode
- **bits_per_pixel**(int) – Number of bits per pixel. Values 1, 2, 4, 8, 16, 24, and 32 are supported;
- **element_size**(int) – Number of bytes per element. Values of 1, 2, and 4 are supported, except that 24 `bits_per_pixel` requires 1 byte per element.
- **reverse_pixels_in_element**(bool) – If set, the first pixel in a word is taken from the Most Significant Bits; otherwise, it is taken from the Least Significant Bits.
- **swap_bytes_in_element**(bool) – If the `element_size` is not 1, then reverse the byte order of each element read.
- **reverse_rows**(bool) – Reverse the direction of the row loading (required for some bitmap images).

```python
class bitmaptools.DitherAlgorithm

Atkinson : DitherAlgorithm

The classic Atkinson dither, often associated with the Hypercard esthetic

FloydStenberg : DitherAlgorithm

The Floyd-Stenberg dither
```


Convert the input image into a 2-level output image using the given dither algorithm.

**Parameters**

- **dest_bitmap**(bitmap) – Destination bitmap. It must have a value_count of 2 or 65536. The stored values are 0 and the maximum pixel value.
- **source_bitmap**(bitmap) – Source bitmap that contains the graphical region to be dithered. It must have a value_count of 65536.
- **colorspace** – The colorspace of the image. The supported colorspaces are RGB565, BGR565, RGB565_SWAPPED, and BGR565_SWAPPED
- **algorithm** – The dither algorithm to use, one of the `DitherAlgorithm` values.
bitops – Routines for low-level manipulation of binary data

bitops.bit_transpose(input: circuitpython_typing.ReadableBuffer, output: circuitpython_typing.WriteableBuffer, width: int = 8) → circuitpython_typing.WriteableBuffer

“Transpose” a buffer by assembling each output byte with bits taken from each of width different input bytes. This can be useful to convert a sequence of pixel values into a single stream of bytes suitable for sending via a parallel conversion method.

The number of bytes in the input buffer must be a multiple of the width, and the width can be any value from 2 to 8. If the width is fewer than 8, then the remaining (less significant) bits of the output are set to zero.

Let \( \text{stride} = \frac{\text{len}(\text{input})}{\text{width}} \). Then the first byte is made out of the most significant bits of \([\text{input}[0], \text{input}[\text{stride}], \text{input}[2*\text{stride}], \ldots]\). The second byte is made out of the second bits, and so on until the 8th output byte which is made of the first bits of \(\text{input}[1], \text{input}[1+\text{stride}, \text{input}[2*\text{stride}], \ldots] \).

The required output buffer size is \(\text{len}(\text{input}) \times 8 \div \text{width}\).

Returns the output buffer.

board – Board specific pin names

Common container for board base pin names. These will vary from board to board so don’t expect portability when using this module.

Another common use of this module is to use serial communication busses with the default pins and settings. For more information about serial communication in CircuitPython, see the busio.

For more information regarding the typical usage of board, refer to the CircuitPython Essentials Learn guide

**Warning:** The board module varies by board. The APIs documented here may or may not be available on a specific board.

board.board_id :str

Board ID string. The unique identifier for the board model in circuitpython, as well as on circuitpython.org. Example: “hallowing_m0_express”.

doctor.I2C() → busio.I2C

Returns the busio.I2C object for the board’s designated I2C bus(es). The object created is a singleton, and uses the default parameter values for busio.I2C.

board.SPI() → busio.SPI

Returns the busio.SPI object for the board’s designated SPI bus(es). The object created is a singleton, and uses the default parameter values for busio.SPI.

board.UART() → busio.UART

Returns the busio.UART object for the board’s designated UART bus(es). The object created is a singleton, and uses the default parameter values for busio.UART.
The `busio` module contains classes to support a variety of serial protocols.

When the microcontroller does not support the behavior in a hardware accelerated fashion it may internally use a bitbang routine. However, if hardware support is available on a subset of pins but not those provided, then a `RuntimeError` will be raised. Use the `bitbangio` module to explicitly bitbang a serial protocol on any general purpose pins.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See `Lifetime and Context Managers` for more info.

For example:

```python
import busio
from board import *

i2c = busio.I2C(SCL, SDA)
print(i2c.scan())
i2c.deinit()
```

This example will initialize the device, run `scan()` and then `deinit()` the hardware. The last step is optional because CircuitPython automatically resets hardware after a program finishes.

Note that drivers will typically handle communication if provided the bus instance (such as `busio.I2C(board.SCL, board.SDA)`), and that many of the methods listed here are lower level functionalities that are needed for working with custom drivers.

**Tutorial for I2C and SPI:** https://learn.adafruit.com/circuitpython-basics-i2c-and-spi

**Tutorial for UART:** https://learn.adafruit.com/circuitpython-essentials/circuitpython-uart-serial


Two wire serial protocol

I2C is a two-wire protocol for communicating between devices. At the physical level it consists of 2 wires: SCL and SDA, the clock and data lines respectively.

**See also:**
Using this class directly requires careful lock management. Instead, use `I2CDevice` to manage locks.

**See also:**
Using this class to directly read registers requires manual bit unpacking. Instead, use an existing driver or make one with `Register` data descriptors.

**Parameters**

- `scl (Pin)` – The clock pin
- `sda (Pin)` – The data pin
- `frequency (int)` – The clock frequency in Hertz
- `timeout (int)` – The maximum clock stretching timeout - (used only for `bitbangio.I2C`; ignored for `busio.I2C`)

**deinit() → None**

Releases control of the underlying hardware so other classes can use it.
__enter__() → I2C
No-op used in Context Managers.

__exit__() → None
Automatically deinitializes the hardware on context exit. See Lifetime and Context Managers for more info.

scan() → List[int]
Scan all I2C addresses between 0x08 and 0x77 inclusive and return a list of those that respond.

   Returns
   List of device ids on the I2C bus

   Return type
   list

try_lock() → bool
Attempts to grab the I2C lock. Returns True on success.

   Returns
   True when lock has been grabbed

   Return type
   bool

unlock() → None
 Releases the I2C lock.

readfrom_into(address: int, buffer: circuitpython_typing.WriteableBuffer, *, start: int = 0, end: int = sys.maxsize) → None
Read into buffer from the device selected by address. At least one byte must be read.
If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed, but without copying the data. The number of bytes read will be the length of buffer[start:end].

Parameters

• address (int) – 7-bit device address
• buffer (WriteableBuffer) – buffer to write into
• start (int) – beginning of buffer slice
• end (int) – end of buffer slice; if not specified, use len(buffer)

writeto(address: int, buffer: circuitpython_typing.ReadableBuffer, *, start: int = 0, end: int = sys.maxsize) → None
Write the bytes from buffer to the device selected by address and then transmit a stop bit.
If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed, but without copying the data. The number of bytes written will be the length of buffer[start:end].
Writing a buffer or slice of length zero is permitted, as it can be used to poll for the existence of a device.

Parameters

• address (int) – 7-bit device address
• buffer (ReadableBuffer) – buffer containing the bytes to write
• start (int) – beginning of buffer slice
• end (int) – end of buffer slice; if not specified, use len(buffer)
writeto_then_readfrom(address: int, out_buffer: circuitpython_typing.ReadableBuffer, in_buffer: circuitpython_typing.WriteableBuffer, *, out_start: int = 0, out_end: int = sys.maxsize, in_start: int = 0, in_end: int = sys.maxsize) → None

Write the bytes from `out_buffer` to the device selected by `address`, generate no stop bit, generate a repeated start and read into `in_buffer`. `out_buffer` and `in_buffer` can be the same buffer because they are used sequentially.

If `out_start` or `out_end` is provided, then the buffer will be sliced as if `out_buffer[out_start:out_end]` were passed, but without copying the data. The number of bytes written will be the length of `out_buffer[out_start:end]`.

If `in_start` or `in_end` is provided, then the input buffer will be sliced as if `in_buffer[in_start:in_end]` were passed. The number of bytes read will be the length of `out_buffer[in_start:in_end]`.

Parameters

- `address` (`int`) – 7-bit device address
- `out_buffer` (`ReadableBuffer`) – buffer containing the bytes to write
- `in_buffer` (`WriteableBuffer`) – buffer to write into
- `out_start` (`int`) – beginning of `out_buffer` slice
- `out_end` (`int`) – end of `out_buffer` slice; if not specified, use `len(out_buffer)`
- `in_start` (`int`) – beginning of `in_buffer` slice
- `in_end` (`int`) – end of `in_buffer` slice; if not specified, use `len(in_buffer)`


A 3-4 wire serial protocol

SPI is a serial protocol that has exclusive pins for data in and out of the main device. It is typically faster than I2C because a separate pin is used to select a device rather than a transmitted address. This class only manages three of the four SPI lines: `clock`, `MOSI`, `MISO`. Its up to the client to manage the appropriate select line, often abbreviated CS or SS. (This is common because multiple secondaries can share the `clock`, `MOSI` and `MISO` lines and therefore the hardware.)

Construct an SPI object on the given pins.

Note: The SPI peripherals allocated in order of desirability, if possible, such as highest speed and not shared use first. For instance, on the nRF52840, there is a single 32MHz SPI peripheral, and multiple 8MHz peripherals, some of which may also be used for I2C. The 32MHz SPI peripheral is returned first, then the exclusive 8MHz SPI peripheral, and finally the shared 8MHz peripherals.

See also:

Using this class directly requires careful lock management. Instead, use SPIDevice to manage locks.

See also:

Using this class to directly read registers requires manual bit unpacking. Instead, use an existing driver or make one with Register data descriptors.

Parameters

- `clock` (`Pin`) – the pin to use for the clock.
• **MOSI** *(Pin)* – the Main Out Selected In pin.

• **MISO** *(Pin)* – the Main In Selected Out pin.

• **half_duplex** *(bool)* – True when MOSI is used for bidirectional data. False when SPI is full-duplex or simplex.

**Limitations:** half_duplex is available only on STM; other chips do not have the hardware support.

**frequency** :**int**

The actual SPI bus frequency. This may not match the frequency requested due to internal limitations.

**deinit()** → None

Turn off the SPI bus.

**__enter__**() → **SPI**

No-op used by Context Managers. Provided by context manager helper.

**__exit__**() → None

Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

**configure**(*, baudrate: int = 100000, polarity: int = 0, phase: int = 0, bits: int = 8) → None

Configures the SPI bus. The SPI object must be locked.

**Parameters**

- **baudrate** *(int)* – the desired clock rate in Hertz. The actual clock rate may be higher or lower due to the granularity of available clock settings. Check the *frequency* attribute for the actual clock rate.

- **polarity** *(int)* – the base state of the clock line (0 or 1)

- **phase** *(int)* – the edge of the clock that data is captured. First (0) or second (1). Rising or falling depends on clock polarity.

- **bits** *(int)* – the number of bits per word

**Note:** On the SAMD21, it is possible to set the baudrate to 24 MHz, but that speed is not guaranteed to work. 12 MHz is the next available lower speed, and is within spec for the SAMD21.

**Note:** On the nRF52840, these baudrates are available: 125kHz, 250kHz, 1MHz, 2MHz, 4MHz, and 8MHz. If you pick a baudrate other than one of these, the nearest lower baudrate will be chosen, with a minimum of 125kHz. Two SPI objects may be created, except on the Circuit Playground Bluefruit, which allows only one (to allow for an additional I2C object).

**try_lock()** → **bool**

Attempts to grab the SPI lock. Returns True on success.

**Returns**

True when lock has been grabbed

**Return type**

**bool**

**unlock()** → None

Releases the SPI lock.
write\((buffer: \text{circuitpython\_typing.ReadableBuffer}, *, \text{start: int} = 0, \text{end: int} = \text{sys.maxsize})\) \rightarrow \text{None}

Write the data contained in buffer. The SPI object must be locked. If the buffer is empty, nothing happens.

If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed, but without copying the data. The number of bytes written will be the length of buffer[start:end].

Parameters

- buffer (ReadableBuffer) – write out bytes from this buffer
- start (int) – beginning of buffer slice
- end (int) – end of buffer slice; if not specified, use \(\text{len(buffer)}\)

readinto\((buffer: \text{circuitpython\_typing.WriteableBuffer}, *, \text{start: int} = 0, \text{end: int} = \text{sys.maxsize}, \text{write\_value: int} = 0\) \rightarrow \text{None}

Read into buffer while writing write\_value for each byte read. The SPI object must be locked. If the number of bytes to read is 0, nothing happens.

If start or end is provided, then the buffer will be sliced as if buffer[start:end] were passed. The number of bytes read will be the length of buffer[start:end].

Parameters

- buffer (WriteableBuffer) – read bytes into this buffer
- start (int) – beginning of buffer slice
- end (int) – end of buffer slice; if not specified, it will be the equivalent value of \(\text{len(buffer)}\) and for any value provided it will take the value of \(\text{min(end, len(buffer))}\)
- write\_value (int) – value to write while reading

write\_readinto\((\text{out\_buffer: \text{circuitpython\_typing.ReadableBuffer}}, \text{in\_buffer: \text{circuitpython\_typing.WriteableBuffer}}, *, \text{out\_start: int} = 0, \text{out\_end: int} = \text{sys.maxsize}, \text{in\_start: int} = 0, \text{in\_end: int} = \text{sys.maxsize})\) \rightarrow \text{None}

Write out the data in out\_buffer while simultaneously reading data into in\_buffer. The SPI object must be locked.

If out\_start or out\_end is provided, then the buffer will be sliced as if out\_buffer[out\_start:out\_end] were passed, but without copying the data. The number of bytes written will be the length of out\_buffer[out\_start:out\_end].

If in\_start or in\_end is provided, then the input buffer will be sliced as if in\_buffer[in\_start:in\_end] were passed. The number of bytes read will be the length of out\_buffer[in\_start:in\_end].

The lengths of the slices defined by out\_buffer[out\_start:out\_end] and in\_buffer[in\_start:in\_end] must be equal. If buffer slice lengths are both 0, nothing happens.

Parameters

- out\_buffer (ReadableBuffer) – write out bytes from this buffer
- in\_buffer (WriteableBuffer) – read bytes into this buffer
- out\_start (int) – beginning of out\_buffer slice
- out\_end (int) – end of out\_buffer slice; if not specified, use \(\text{len(out\_buffer)}\)
- in\_start (int) – beginning of in\_buffer slice
- in\_end (int) – end of in\_buffer slice; if not specified, use \(\text{len(in\_buffer)}\)

A bidirectional serial protocol

A common bidirectional serial protocol that uses an agreed upon speed rather than a shared clock line.

Parameters

• tx (Pin) – the pin to transmit with, or None if this UART is receive-only.
• rx (Pin) – the pin to receive on, or None if this UART is transmit-only.
• rts (Pin) – the pin for rts, or None if rts not in use.
• cts (Pin) – the pin for cts, or None if cts not in use.
• rs485_dir (Pin) – the output pin for rs485 direction setting, or None if rs485 not in use.
• rs485_invert (bool) – rs485_dir pin active high when set. Active low otherwise.
• baudrate (int) – the transmit and receive speed.
• bits (int) – the number of bits per byte, 5 to 9.
• parity (Parity) – the parity used for error checking.
• stop (int) – the number of stop bits, 1 or 2.
• timeout (float) – the timeout in seconds to wait for the first character and between subsequent characters when reading. Raises ValueError if timeout >100 seconds.
• receiver_buffer_size (int) – the character length of the read buffer (0 to disable). (When a character is 9 bits the buffer will be 2 * receiver_buffer_size bytes.)

New in CircuitPython 4.0: timeout has incompatibly changed units from milliseconds to seconds. The new upper limit on timeout is meant to catch mistaken use of milliseconds.

Limitations: RS485 is not supported on SAMD, nRF, Broadcom, Spresense, or STM. On i.MX and Raspberry Pi RP2040 support is implemented in software: The timing for the rs485_dir pin signal is done on a best-effort basis, and may not meet RS485 specifications intermittently.

baudrate :int

The current baudrate.

in_waiting :int

The number of bytes in the input buffer, available to be read

timeout :float

The current timeout, in seconds (float).

deinit() → None

Deinitialises the UART and releases any hardware resources for reuse.

__enter__() → UART

No-op used by Context Managers.

__exit__() → None

Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.
read(nbytes: Optional[int] = None) → Optional[bytes]

Read bytes. If nbytes is specified then read at most that many bytes. Otherwise, read everything that arrives until the connection times out. Providing the number of bytes expected is highly recommended because it will be faster. If no bytes are read, return None.

Note: When no bytes are read due to a timeout, this function returns None. This matches the behavior of `io.RawIOBase.read` in Python 3, but differs from pyserial which returns b'' in that situation.

Returns
Data read

Return type
bytes or None

readinto(buf: circuitpython_typing.WriteableBuffer) → Optional[int]

Read bytes into the buf. Read at most len(buf) bytes.

Returns
number of bytes read and stored into buf

Return type
int or None (on a non-blocking error)

New in CircuitPython 4.0: No length parameter is permitted.

readline() → bytes

Read a line, ending in a newline character, or return None if a timeout occurs sooner, or return everything readable if no newline is found and timeout=0

Returns
the line read

Return type
bytes or None

write(buf: circuitpython_typing.ReadableBuffer) → Optional[int]

Write the buffer of bytes to the bus.

New in CircuitPython 4.0: buf must be bytes, not a string.

return
the number of bytes written

rtype
int or None

reset_input_buffer() → None

Discard any unread characters in the input buffer.

class busio.Parity

Enum-like class to define the parity used to verify correct data transfer.

ODD :int
Total number of ones should be odd.

EVEN :int
Total number of ones should be even.
camera – Support for camera input

The camera module contains classes to control the camera and take pictures.

class camera.Camera

The class to control camera.

Usage:

```python
import board
import sdioio
import storage
import camera

sd = sdioio.SDCard(
    clock=board.SDIO_CLOCK,
    command=board.SDIO_COMMAND,
    data=board.SDIO_DATA,
    frequency=25000000)

vfs = storage.VfsFat(sd)
storage.mount(vfs, '/sd')

cam = camera.Camera()

buffer = bytearray(512 * 1024)
file = open('/sd/image.jpg','wb')
size = cam.take_picture(buffer, width=1920, height=1080, format=camera.ImageFormat.JPG)
file.write(buffer, size)
file.close()
```

Initialize camera.

definit() → None

De-initialize camera.

take_picture(buf: circuitpython_typing.WriteableBuffer, format: ImageFormat) → int

Take picture and save to buf in the given format. The size of the picture taken is width by height in pixels.

Returns

the number of bytes written into buf

Return type

int

class camera.ImageFormat

Image format

Enum-like class to define the image format.

JPG :ImageFormat

JPG format.

RGB565 :ImageFormat

RGB565 format.
canio – CAN bus access

The canio module contains low level classes to support the CAN bus protocol.

CAN and Listener classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See Lifetime and ContextManagers for more info.

For example:

```python
import canio
from board import *

can = canio.CAN(board.CAN_RX, board.CAN_TX, baudrate=1000000)
message = canio.Message(id=0x0408, data=b"adafruit")
can.send(message)
can.deinit()
```

This example will write the data ‘adafruit’ onto the CAN bus to any device listening for message id 0x0408.

A CAN bus involves a transceiver, which is often a separate chip with a “standby” pin. If your board has a CAN_STANDBY pin, ensure to set it to an output with the value False to enable the transceiver.

Other implementations of the CAN device may exist (for instance, attached via an SPI bus). If so their constructor arguments may differ, but otherwise we encourage implementors to follow the API that the core uses.

For more information on working with this module, refer to this Learn Guide on using it.

```python

class canio.BusState
    The state of the CAN bus

    ERROR_ACTIVE : object
        The bus is in the normal (active) state

    ERROR_WARNING : object
        The bus is in the normal (active) state, but a moderate number of errors have occurred recently.

    Note: Not all implementations may use ERROR_WARNING. Do not rely on seeing ERROR_WARNING before ERROR_PASSIVE.

    ERROR_PASSIVE : object
        The bus is in the passive state due to the number of errors that have occurred recently.

        This device will acknowledge packets it receives, but cannot transmit messages. If additional errors occur, this device may progress to BUS_OFF. If it successfully acknowledges other packets on the bus, it can return to ERROR_WARNING or ERROR_ACTIVE and transmit packets.

    BUS_OFF : object
        The bus has turned off due to the number of errors that have occurred recently. It must be restarted before it will send or receive packets. This device will neither send or acknowledge packets on the bus.


    CAN bus protocol

    A common shared-bus protocol. The rx and tx pins are generally connected to a transceiver which controls the H and L pins on a shared bus.
```
Parameters

- **rx** *(Pin)* – the pin to receive with
- **tx** *(Pin)* – the pin to transmit with
- **baudrate** *(int)* – The bit rate of the bus in Hz. All devices on the bus must agree on this value.
- **loopback** *(bool)* – When True the rx pin’s value is ignored, and the device receives the packets it sends.
- **silent** *(bool)* – When True the tx pin is always driven to the high logic level. This mode can be used to “sniff” a CAN bus without interfering.
- **auto_restart** *(bool)* – If True, will restart communications after entering bus-off state

```python
auto_restart : bool
    If True, will restart communications after entering bus-off state
```

```python
baudrate : int
    The baud rate (read-only)
```

```python
transmit_error_count : int
    The number of transmit errors (read-only). Increased for a detected transmission error, decreased for successful transmission. Limited to the range from 0 to 255 inclusive. Also called TEC.
```

```python
receive_error_count : int
    The number of receive errors (read-only). Increased for a detected reception error, decreased for successful reception. Limited to the range from 0 to 255 inclusive. Also called REC.
```

```python
state : BusState
    The current state of the bus. (read-only)
```

```python
loopback : bool
    True if the device was created in loopback mode, False otherwise (read-only)
```

```python
silent : bool
    True if the device was created in silent mode, False otherwise (read-only)
```

```python
restart() → None
    If the device is in the bus off state, restart it.
```

```python
listen(matches: Optional[Sequence[Match]] = None, *, timeout: float = 10) → Listener
    Start receiving messages that match any one of the filters.
```

Creating a listener is an expensive operation and can interfere with reception of messages by other listeners. There is an implementation-defined maximum number of listeners and limit to the complexity of the filters. If the hardware cannot support all the requested matches, a ValueError is raised. Note that generally there are some number of hardware filters shared among all fifos. A message can be received by at most one Listener. If more than one listener matches a message, it is undefined which one actually receives it. An empty filter list causes all messages to be accepted. Timeout dictates how long receive() and next() will block.

Platform specific notes:
SAM E5x supports two Listeners. Filter blocks are shared between the two listeners. There are 4 standard filter blocks and 4 extended filter blocks. Each block can either match 2 single addresses or a mask of addresses. The number of filter blocks can be increased, up to a hardware maximum, by rebuilding CircuitPython, but this decreases the CircuitPython free memory even if canio is not used.

STM32F405 supports two Listeners. Filter blocks are shared between the two listeners. There are 14 filter blocks. Each block can match 2 standard addresses with mask or 1 extended address with mask.

ESP32S2 supports one Listener. There is a single filter block, which can either match a standard address with mask or an extended address with mask.

```python
send(message: Union[RemoteTransmissionRequest, Message]) → None
```

Send a message on the bus with the given data and id. If the message could not be sent due to a full fifo or a bus error condition, RuntimeError is raised.

```python
deinit() → None
```

Deinitialize this object, freeing its hardware resources

```python
__enter__() → CAN
```

Returns self, to allow the object to be used in a The with statement statement for resource control

```python
__exit__(unused1: Optional[Type[BaseException]], unused2: Optional[BaseException], unused3: Optional[types.TracebackType]) → None
```

Calls deinit()

```python
class canio.Listener
```

Listens for CAN message

`canio.Listener` is not constructed directly, but instead by calling `canio.CAN.listen`.

In addition to using the `receive` method to retrieve a message or the `in_waiting` method to check for an available message, a listener can be used as an iterable, yielding messages until no message arrives within `self.timeout` seconds.

```python
timeout : float
```

```python
receive() → Optional[Union[RemoteTransmissionRequest, Message]]
```

Reads a message, after waiting up to `self.timeout` seconds

If no message is received in time, `None` is returned. Otherwise, a `Message` or `RemoteTransmissionRequest` is returned.

```python
in_waiting() → int
```

Returns the number of messages (including remote transmission requests) waiting

```python
__iter__() → Listener
```

Returns self

This method exists so that `Listener` can be used as an iterable

```python
__next__() → Union[RemoteTransmissionRequest, Message]
```

Reads a message, after waiting up to `self.timeout` seconds

If no message is received in time, raises StopIteration. Otherwise, a Message or is returned.

This method enables the `Listener` to be used as an iterable, for instance in a for-loop.

```python
deinit() → None
```

Deinitialize this object, freeing its hardware resources
__enter__(self) -> CAN

Returns self, to allow the object to be used in a `with` statement for resource control.

__exit__(self, unused1: Optional[Type[BaseException]], unused2: Optional[BaseException], unused3: Optional[types.TracebackType]) -> None

Calls deinit().

class canio.Match(id: int, *, mask: Optional[int] = None, extended: bool = False)

Describe CAN bus messages to match.

Construct a Match with the given properties.

If mask is not None, then the filter is for any id which matches all the nonzero bits in mask. Otherwise, it matches exactly the given id. If extended is true then only extended ids are matched, otherwise only standard ids are matched.

id : int
    The id to match

mask : int
    The optional mask of ids to match

extended : bool
    True to match extended ids, False to match standard ids

class canio.Message(id: int, data: bytes, *, extended: bool = False)

Construct a Message to send on a CAN bus.

Parameters

• id (int) – The numeric ID of the message
• data (bytes) – The content of the message
• extended (bool) – True if the message has an extended identifier, False if it has a standard identifier

In CAN, messages can have a length from 0 to 8 bytes.

id : int
    The numeric ID of the message

data : bytes
    The content of the message

extended : bool
    True if the message’s id is an extended id

class canio.RemoteTransmissionRequest(id: int, length: int, *, extended: bool = False)

Construct a RemoteTransmissionRequest to send on a CAN bus.

Parameters

• id (int) – The numeric ID of the requested message
• length (int) – The length of the requested message
• extended (bool) – True if the message has an extended identifier, False if it has a standard identifier

In CAN, messages can have a length from 0 to 8 bytes.
id : int
    The numeric ID of the message
extended : bool
    True if the message’s id is an extended id
length : int
    The length of the requested message.

coproc – COPROC Module

The `coproc` module adds ability to load and run programs on a co-processor or a different cpu core.

```python
import coproc

shared_mem = coproc.CoprocMemory(address=0x500007fc, length=1024)

with open("program.bin", "rb") as f:
    program = coproc.Coproc(buffer=f.read(), memory=shared_mem)

coproc.run(program)
print(coproc.memory(program)[0])  # coproc.halt(program)
```

coproc.run(*coproc: Coproc) → None
    Runs the loaded program.

coproc.halt(*coproc: Coproc) → None
    Halts the loaded program.

coproc.memory(*coproc: Coproc) → CoprocMemory
    Returns the shared memory as a bytearray.

class coproc.Coproc(buffer: circuitpython_typing.ReadableBuffer, memory: CoprocMemory)
    Loads the program binary into memory.
    Parameters
    • buffer – The program binary to run on the core/co-processor
    • memory – The CoprocMemory object used to access shared memory
deinit() → None
    Releases control of the underlying hardware so other classes can use it.
__enter__() → Coproc
    No-op used in Context Managers.
__exit__() → None
    Close the request.

class coproc.CoprocMemory(address: int, length: int)
    Initialize coproc shared memory.
    Parameters
    • address – address of shared memory
• **length** – length of shared memory

    __bool__() → bool
    
    `coproc_memory` is True if its length is greater than zero. This is an easy way to check for its existence.

    __len__() → int
    
    Return the length. This is used by (`len`)

    __getitem__(index: slice) → bytearray
    __getitem__(index: int) → int
    
    Returns the value at the given index.

    __setitem__(index: slice, value: circuitpython_typing.ReadableBuffer) → None
    __setitem__(index: int, value: int) → None
    
    Set the value at the given index.

**countio** – Support for edge counting

The `countio` module contains logic to read and count edge transitions.

For more information on the applications of counting edges, see this Learn Guide on sequential circuits.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See *Lifetime and Context Managers* for more info.

**class** `countio.Edge`

    Enumerates which signal transitions can be counted.

    Enum-like class to define which signal transitions to count.

    **RISE** : Edge
    
    Count the rising edges.

    **FALL** : Edge
    
    Count the falling edges.

    **RISE_AND_FALL** : Edge
    
    Count the rising and falling edges.

    **Limitations:** `RISE_AND_FALL` is not available to RP2040 due to hardware limitations.


    Count the number of rising- and/or falling-edge transitions on a given pin.

    Create a Counter object associated with the given pin that counts rising- and/or falling-edge transitions. At least one of `rise` and `fall` must be True. The default is to count only falling edges, and is for historical backward compatibility.

    **Parameters**

      • **pin** (Pin) – pin to monitor
      • **edge** (Edge) – which edge transitions to count
      • **pull** (Optional[digitalio.Pull]) – enable a pull-up or pull-down if not None

    For example:
```python
import board
import countio

# Count rising edges only.
pin_counter = countio.Counter(board.D1, edge=countio.Edge.RISE)
# Reset the count after 100 counts.
while True:
    if pin_counter.count >= 100:
        pin_counter.reset()
    print(pin_counter.count)
```

**count**: int

The current count in terms of pulses.

**deinit** → None

Deinitializes the Counter and releases any hardware resources for reuse.

**__enter__** → Counter

No-op used by Context Managers.

**__exit__** → None

Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

**reset** → None

Resets the count back to 0.

cyw43 – A class that represents a GPIO pin attached to the wifi chip.

class cyw43.CywPin

Cannot be constructed at runtime, but may be the type of a pin object in *board*. A *CywPin* can be used as a *DigitalInOut*, but not with other peripherals such as *PWMOut*.

cyw43.PM_STANDARD :int

The standard power management mode

cyw43.PM_AGGRESSIVE :int

Aggressive power management mode for optimal power usage at the cost of performance

cyw43.PM_PERFORMANCE :int

Performance power management mode where more power is used to increase performance

cyw43.PM_DISABLED :int

Disable power management and always use highest power mode. CircuitPython sets this value at reset time, because it provides the best connectivity reliability.

cyw43.set_power_management(value: int) → None

Set the power management register

For transmitter power, see *wifi.Radio.txpower*. This controls software power saving features inside the cyw43 chip. it does not control transmitter power.

The value is interpreted as a 24-bit hexadecimal number of the form 0x00adbrrm.

The low 4 bits, m, are the power management mode:
The next 8 bits, \( r \), specify “the maximum time to wait before going back to sleep” for power management mode 2. The units of \( r \) are 10ms.

The next 4 bits, \( b \), are the “wake period is measured in beacon periods”.

The next 4 bits, \( d \), specify the “wake interval measured in DTIMs. If this is set to 0, the wake interval is measured in beacon periods”.

The top 4 bits, \( a \), specifies the “wake interval sent to the access point”

Several PM_ constants gathered from various sources are included in this module. According to Raspberry Pi documentation, the value 0xa11140 (called `cyw43.PM_DISABLED` here) increases responsiveness at the cost of higher power usage.

```python
import cyw43

cyw43.get_power_management() -> int
```

Retrieve the power management register

digitalio – Basic digital pin support

The `digitalio` module contains classes to provide access to basic digital IO.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See `Lifetime and ContextManagers` for more info.

For example:

```python
import digitalio
import board

pin = digitalio.DigitalInOut(board.LED)
print(pin.value)
```

This example will initialize the the device, read `value` and then `deinit()` the hardware.

Here is blinky:

```python
import time
import digitalio
import board

led = digitalio.DigitalInOut(board.LED)
led.direction = digitalio.Direction.OUTPUT

while True:
    led.value = True
    time.sleep(0.1)
    led.value = False
    time.sleep(0.1)
```

For the essentials of `digitalio`, see the CircuitPython Essentials Learn guide

For more information on using `digitalio`, see this additional Learn guide
class digitalio.DriveMode

Defines the drive mode of a digital pin

- **PUSH_PULL** :DriveMode
  - Output both high and low digital values
- **OPEN_DRAIN** :DriveMode
  - Output low digital values but go into high z for digital high. This is useful for i2c and other protocols that share a digital line.

class digitalio.DigitalInOut(pin: microcontroller.Pin)

Digital input and output

A DigitalInOut is used to digitally control I/O pins. For analog control of a pin, see the analogio.AnalogIn and analogio.AnalogOut classes.

Create a new DigitalInOut object associated with the pin. Defaults to input with no pull. Use switch_to_input() and switch_to_output() to change the direction.

**Parameters**
- **pin** *(Pin)* – The pin to control
- **direction** :Direction
  - The direction of the pin.
  - Setting this will use the defaults from the corresponding switch_to_input() or switch_to_output() method. If you want to set pull, value or drive mode prior to switching, then use those methods instead.
- **value** :bool
  - The digital logic level of the pin.
- **drive_mode** :DriveMode
  - The pin drive mode. One of:
    - *digitalio.DriveMode.PUSH_PULL*
    - *digitalio.DriveMode.OPEN_DRAIN*
- **pull** :Optional[Pull]
  - The pin pull direction. One of:
    - *digitalio.Pull.UP*
    - *digitalio.Pull.DOWN*
    - *None*

**Raises**
- **AttributeError** – if **direction** is **OUTPUT**.

definit() ➔ None

Turn off the DigitalInOut and release the pin for other use.

__enter__() ➔ DigitalInOut

No-op used by Context Managers.

__exit__() ➔ None

Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.
**switch_to_output**(value: bool = False, drive_mode: DriveMode = DriveMode.PUSH_PULL) → None

Set the drive mode and value and then switch to writing out digital values.

**Parameters**

- **value**(bool) – default value to set upon switching
- **drive_mode**(DriveMode) – drive mode for the output

**switch_to_input**(pull: Optional[Pull] = None) → None

Set the pull and then switch to read in digital values.

**Parameters**

- **pull**(Pull) – pull configuration for the input

Example usage:

```python
import digitalio
import board

switch = digitalio.DigitalInOut(board.SLIDE_SWITCH)
switch.switch_to_input(pull=digitalio.Pull.UP)
# Or, after switch_to_input
switch.pull = digitalio.Pull.UP
print(switch.value)
```

**class digitalio.**Direction

Defines the direction of a digital pin

Enum-like class to define which direction the digital values are going.

**INPUT** :Direction

Read digital data in

**OUTPUT** :Direction

Write digital data out

**class digitalio.**Pull

Defines the pull of a digital input pin

Enum-like class to define the pull value, if any, used while reading digital values in.

**UP** :Pull

When the input line isn’t being driven the pull up can pull the state of the line high so it reads as true.

**DOWN** :Pull

When the input line isn’t being driven the pull down can pull the state of the line low so it reads as false.

**displayio – Native helpers for driving displays**

The `displayio` module contains classes to manage display output including synchronizing with refresh rates and partial updating.

For more a more thorough explanation and guide for using `displayio`, please refer to this Learn guide.
displayio.release_displays() → None

Releases any actively used displays so their busses and pins can be used again. This will also release the built-in display on boards that have one. You will need to reinitialize it yourself afterwards. This may take seconds to complete if an active EPaperDisplay is refreshing.

Use this once in your code.py if you initialize a display. Place it right before the initialization so the display is active as long as possible.

class displayio.Colorspace

The colorspace for a ColorConverter to operate in

RGB888 : Colorspace

The standard 24-bit colorspace. Bits 0-7 are blue, 8-15 are green, and 16-24 are red. (0xRRGGBB)

RGB565 : Colorspace

The standard 16-bit colorspace. Bits 0-4 are blue, bits 5-10 are green, and 11-15 are red. (0bRRRGGGGGBBBBB)

RGB565_SWAPPED : Colorspace

The swapped 16-bit colorspace. First, the high and low 8 bits of the number are swapped, then they are interpreted as for RGB565

RGB555 : Colorspace

The standard 15-bit colorspace. Bits 0-4 are blue, bits 5-9 are green, and 11-14 are red. The top bit is ignored. (0bRRRRGGGGGBBBBB)

RGB555_SWAPPED : Colorspace

The swapped 15-bit colorspace. First, the high and low 8 bits of the number are swapped, then they are interpreted as for RGB555

class displayio.Bitmap(width: int, height: int, value_count: int)

Stores values of a certain size in a 2D array

Bitmaps can be treated as read-only buffers. If the number of bits in a pixel is 8, 16, or 32; and the number of bytes per row is a multiple of 4, then the resulting memoryview will correspond directly with the bitmap’s contents. Otherwise, the bitmap data is packed into the memoryview with unspecified padding.

A Bitmap can be treated as a buffer, allowing its content to be viewed and modified using e.g., with ulab.numpy.frombuffer, but the displayio.Bitmap.dirty method must be used to inform displayio when a bitmap was modified through the buffer interface.

bitmaptools.arrayblit can also be useful to move data efficiently into a Bitmap.

Create a Bitmap object with the given fixed size. Each pixel stores a value that is used to index into a corresponding palette. This enables differently colored sprites to share the underlying Bitmap. value_count is used to minimize the memory used to store the Bitmap.

Parameters

- width (int) – The number of values wide
- height (int) – The number of values high
- value_count (int) – The number of possible pixel values.

width : int

Width of the bitmap. (read only)

height : int

Height of the bitmap. (read only)
__getitem__(index: Union[Tuple[int, int], int]) → int

Returns the value at the given index. The index can either be an x,y tuple or an int equal to \( y \times \text{width} + x \).

This allows you to:

```
print(bitmap[0,1])
```

__setitem__(index: Union[Tuple[int, int], int], value: int) → None

Sets the value at the given index. The index can either be an x,y tuple or an int equal to \( y \times \text{width} + x \).

This allows you to:

```
bitmap[0,1] = 3
```

blit(x: int, y: int, source_bitmap: Bitmap, *, x1: int, y1: int, x2: int, y2: int, skip_index: int) → None

Inserts the source_bitmap region defined by rectangular boundaries \((x1,y1)\) and \((x2,y2)\) into the bitmap at the specified \((x,y)\) location.

**Parameters**

- **x (int)** – Horizontal pixel location in bitmap where source_bitmap upper-left corner will be placed
- **y (int)** – Vertical pixel location in bitmap where source_bitmap upper-left corner will be placed
- **source_bitmap (bitmap)** – Source bitmap that contains the graphical region to be copied
- **x1 (int)** – Minimum x-value for rectangular bounding box to be copied from the source bitmap
- **y1 (int)** – Minimum y-value for rectangular bounding box to be copied from the source bitmap
- **x2 (int)** – Maximum x-value (exclusive) for rectangular bounding box to be copied from the source bitmap
- **y2 (int)** – Maximum y-value (exclusive) for rectangular bounding box to be copied from the source bitmap
- **skip_index (int)** – bitmap palette index in the source that will not be copied, set to None to copy all pixels

fill(value: int) → None

Fills the bitmap with the supplied palette index value.

dirty(x1: int = 0, y1: int = 0, x2: int = -1, y2: int = -1) → None

Inform displayio of bitmap updates done via the buffer protocol.

**Parameters**

- **x1 (int)** – Minimum x-value for rectangular bounding box to be considered as modified
- **y1 (int)** – Minimum y-value for rectangular bounding box to be considered as modified
- **x2 (int)** – Maximum x-value (exclusive) for rectangular bounding box to be considered as modified
- **y2 (int)** – Maximum y-value (exclusive) for rectangular bounding box to be considered as modified
If x1 or y1 are not specified, they are taken as 0. If x2 or y2 are not specified, or are given as -1, they are taken as the width and height of the image. Thus, calling dirty() with the default arguments treats the whole bitmap as modified.

When a bitmap is modified through the buffer protocol, the display will not be properly updated unless the bitmap is notified of the “dirty rectangle” that encloses all modified pixels.

class displayio.ColorConverter(*, input_colorspace: Colorspace = Colorspace.RGB888, dither: bool = False)

Converts one color format to another.

Create a ColorConverter object to convert color formats.

Parameters

• colorspace (Colorspace) – The source colorspace, one of the Colorspace constants

• dither (bool) – Adds random noise to dither the output image

dither :bool

When True the ColorConverter dithers the output by adding random noise when truncating to display bidepth

convert(color: int) → int

Converts the given color to RGB565 according to the Colorspace

make_transparent(color: int) → None

Set the transparent color or index for the ColorConverter. This will raise an Exception if there is already a selected transparent index.

Parameters

color (int) – The color to be transparent

make_opaque(color: int) → None

Make the ColorConverter be opaque and have no transparent pixels.

Parameters

color (int) – [IGNORED] Use any value

class displayio._DisplayBus

FourWire, paralleldisplay.ParallelBus or I2C


Manage updating a display over a display bus

This initializes a display and connects it into CircuitPython. Unlike other objects in CircuitPython, Display objects live until displayio.release_displays() is called. This is done so that CircuitPython can use the display itself.

Most people should not use this class directly. Use a specific display driver instead that will contain the initialization sequence at minimum.
Create a Display object on the given display bus (FourWire, ParallelBus or I2CDisplay).

The init_sequence is bitpacked to minimize the ram impact. Every command begins with a command byte followed by a byte to determine the parameter count and delay. When the top bit of the second byte is 1 (0x80), a delay will occur after the command parameters are sent. The remaining 7 bits are the parameter count excluding any delay byte. The bytes following are the parameters. When the delay bit is set, a single byte after the parameters specifies the delay duration in milliseconds. The value 0xff will lead to an extra long 500 ms delay instead of 255 ms. The next byte will begin a new command definition. Here is an example:

```python
init_sequence = (b"\xe1\x0f\x00\x0e\x14\x03\x11\x07\x31\xC1\x48\x08\x0F\x0C\x31\x36\n\x0F" # Set Gamma
        b"\x11\x80\x78" # Exit Sleep then delay 0x78 (120ms)
        b"\x29\x81\xaa\x78" # Display on then delay 0x78 (120ms)
    )
display = displayio.Display(display_bus, init_sequence, width=320, height=240)
```

The first command is 0xe1 with 15 (0xf) parameters following. The second is 0x11 with 0 parameters and a 120ms (0x78) delay. The third command is 0x29 with one parameter 0xaa and a 120ms delay (0x78). Multiple byte literals (b""") are merged together on load. The parens are needed to allow byte literals on subsequent lines.

The initialization sequence should always leave the display memory access inline with the scan of the display to minimize tearing artifacts.

Parameters

- **display_bus** – The bus that the display is connected to
- **init_sequence** (ReadableBuffer) – Byte-packed initialization sequence.
- **width** (int) – Width in pixels
- **height** (int) – Height in pixels
- **colstart** (int) – The index if the first visible column
- **rowstart** (int) – The index if the first visible row
- **rotation** (int) – The rotation of the display in degrees clockwise. Must be in 90 degree increments (0, 90, 180, 270)
- **color_depth** (int) – The number of bits of color per pixel transmitted. (Some displays support 18 bit but 16 is easier to transmit. The last bit is extrapolated.)
- **grayscale** (bool) – True if the display only shows a single color.
- **pixels_in_byte_share_row** (bool) – True when pixels are less than a byte and a byte includes pixels from the same row of the display. When False, pixels share a column.
- **bytes_per_cell** (int) – Number of bytes per addressable memory location when color_depth < 8. When greater than one, bytes share a row or column according to pixels_in_byte_share_row.
- **reverse_pixels_in_byte** (bool) – Reverses the pixel order within each byte when color_depth < 8. Does not apply across multiple bytes even if there is more than one byte per cell (bytes_per_cell.)
- **reverse_bytes_in_word** (bool) – Reverses the order of bytes within a word when color_depth == 16
- **set_column_command** (int) – Command used to set the start and end columns to update
- **set_row_command** (int) – Command used so set the start and end rows to update
• `write_ram_command (int)` – Command used to write pixels values into the update region. Ignored if data_as_commands is set.

• `backlight_pin (microcontroller.Pin)` – Pin connected to the display’s backlight

• `brightness_command (int)` – Command to set display brightness. Usually available in OLED controllers.

• `brightness (float)` – Initial display brightness.

• `single_byte_bounds (bool)` – Display column and row commands use single bytes

• `data_as_commands (bool)` – Treat all init and boundary data as SPI commands. Certain displays require this.

• `auto_refresh (bool)` – Automatically refresh the screen

• `native_frames_per_second (int)` – Number of display refreshes per second that occur with the given init_sequence.

• `backlight_on_high (bool)` – If True, pulling the backlight pin high turns the backlight on.

• `SH1107_addressing (bool)` – Special quirk for SH1107, use upper/lower column set and page set

• `set_vertical_scroll (int)` – This parameter is accepted but ignored for backwards compatibility. It will be removed in a future release.

• `backlight_pwm_frequency (int)` – The frequency to use to drive the PWM for backlight brightness control. Default is 50000.

`auto_refresh :bool`

  True when the display is refreshed automatically.

`brightness :float`

  The brightness of the display as a float. 0.0 is off and 1.0 is full brightness.

`width :int`

  Gets the width of the board

`height :int`

  Gets the height of the board

`rotation :int`

  The rotation of the display as an int in degrees.

`bus :_DisplayBus`

  The bus being used by the display

`root_group :Group`

  The root group on the display.

`show (group: Group) → None`

  Switches to displaying the given group of layers. When group is None, the default CircuitPython terminal will be shown.

  Parameters

  `group (Group)` – The group to show.
**refresh**(*, **target_frames_per_second**: Optional[int] = None, **minimum_frames_per_second**: int = 0) → bool

When auto_refresh is off, and **target_frames_per_second** is not **None** this waits for the target frame rate and then refreshes the display, returning **True**. If the call has taken too long since the last refresh call for the given target frame rate, then the refresh returns **False** immediately without updating the screen to hopefully help getting caught up.

If the time since the last successful refresh is below the minimum frame rate, then an exception will be raised. The default **minimum_frames_per_second** of 0 disables this behavior.

When auto_refresh is off, and **target_frames_per_second** is **None** this will update the display immediately.

When auto_refresh is on, updates the display immediately. (The display will also update without calls to this.)

**Parameters**

- **target_frames_per_second** (Optional[int]) – The target frame rate that **refresh** should try to achieve. Set to **None** for immediate refresh.
- **minimum_frames_per_second**(int) – The minimum number of times the screen should be updated per second.

**fill_row**(y: int, buffer: circuitpython_typing.WriteableBuffer) → circuitpython_typing.WriteableBuffer

Extract the pixels from a single row

**Parameters**

- **y** (int) – The top edge of the area
- **buffer** (WriteableBuffer) – The buffer in which to place the pixel data


Manage updating an epaper display over a display bus

This initializes an epaper display and connects it into CircuitPython. Unlike other objects in CircuitPython, EPaperDisplay objects live until **displayio.release_displays** is called. This is done so that CircuitPython can use the display itself.

Most people should not use this class directly. Use a specific display driver instead that will contain the startup and shutdown sequences at minimum.

Create a EPaperDisplay object on the given display bus (**displayio.FourWire** or **paralleldisplay.ParallelBus**).
The `start_sequence` and `stop_sequence` are bitpacked to minimize the ram impact. Every command begins with a command byte followed by a byte to determine the parameter count and delay. When the top bit of the second byte is 1 (0x80), a delay will occur after the command parameters are sent. The remaining 7 bits are the parameter count excluding any delay byte. The bytes following are the parameters. When the delay bit is set, a single byte after the parameters specifies the delay duration in milliseconds. The value 0xff will lead to an extra long 500 ms delay instead of 255 ms. The next byte will begin a new command definition.

**Parameters**

- **display_bus** – The bus that the display is connected to
- **start_sequence** (*ReadableBuffer*) – Byte-packed initialization sequence.
- **stop_sequence** (*ReadableBuffer*) – Byte-packed initialization sequence.
- **width** (*int*) – Width in pixels
- **height** (*int*) – Height in pixels
- **ram_width** (*int*) – RAM width in pixels
- **ram_height** (*int*) – RAM height in pixels
- **colstart** (*int*) – The index if the first visible column
- **rowstart** (*int*) – The index if the first visible row
- **rotation** (*int*) – The rotation of the display in degrees clockwise. Must be in 90 degree increments (0, 90, 180, 270)
- **set_column_window_command** (*int*) – Command used to set the start and end columns to update
- **set_row_window_command** (*int*) – Command used so set the start and end rows to update
- **set_current_column_command** (*int*) – Command used to set the current column location
- **set_current_row_command** (*int*) – Command used to set the current row location
- **write_black_ram_command** (*int*) – Command used to write pixels values into the update region
- **black_bits_inverted** (*bool*) – True if 0 bits are used to show black pixels. Otherwise, 1 means to show black.
- **write_color_ram_command** (*int*) – Command used to write pixels values into the update region
- **color_bits_inverted** (*bool*) – True if 0 bits are used to show the color. Otherwise, 1 means to show color.
- **highlight_color** (*int*) – RGB888 of source color to highlight with third ePaper color.
- **refresh_display_command** (*int*) – Command used to start a display refresh
- **refresh_time** (*float*) – Time it takes to refresh the display before the stop_sequence should be sent. Ignored when busy_pin is provided.
- **busy_pin** (*microcontroller.Pin*) – Pin used to signify the display is busy
- **busy_state** (*bool*) – State of the busy pin when the display is busy
- **seconds_per_frame** (*float*) – Minimum number of seconds between screen refreshes
- **always_toggle_chip_select** (*bool*) – When True, chip select is toggled every byte
- **grayscale** (*bool*) – When true, the color ram is the low bit of 2-bit grayscale
• **two_byte_sequence_length** *(bool)* – When true, use two bytes to define sequence length

**time_to_refresh** : float
Time, in fractional seconds, until the ePaper display can be refreshed.

**busy** : bool
True when the display is refreshing. This uses the busy_pin when available or the refresh_time otherwise.

**width** : int
Gets the width of the display in pixels

**height** : int
Gets the height of the display in pixels

**rotation** : int
The rotation of the display as an int in degrees.

**bus** : DisplayBus
The bus being used by the display

**show** *(group: Group) → None*
Switches to displaying the given group of layers. When group is None, the default CircuitPython terminal will be shown.

**Parameters**
- **group** *(Group)* – The group to show.

**update_refresh_mode** *(start_sequence: circuitpython_typing.ReadableBuffer, seconds_per_frame: float = 180) → None*
Updates the start_sequence and seconds_per_frame parameters to enable varying the refresh mode of the display.

**refresh() → None**
Refreshes the display immediately or raises an exception if too soon. Use time.sleep(display.time_to_refresh) to sleep until a refresh can occur.

Manage updating a display over SPI four wire protocol in the background while Python code runs. It doesn’t handle display initialization.

Create a FourWire object associated with the given pins.

The SPI bus and pins are then in use by the display until **displayio.release_displays()** is called even after a reload. (It does this so CircuitPython can use the display after your code is done.) So, the first time you initialize a display bus in code.py you should call **displayio.release_displays()** first, otherwise it will error after the first code.py run.

If the **command** pin is not specified, a 9-bit SPI mode will be simulated by adding a data/command bit to every bit being transmitted, and splitting the resulting data back into 8-bit bytes for transmission. The extra bits that this creates at the end are ignored by the receiving device.

**Parameters**
- **spi_bus** *(busio.SPI)* – The SPI bus that make up the clock and data lines
- **command** *(microcontroller.Pin)* – Data or command pin. When None, 9-bit SPI is simulated.
• **chip_select** ([microcontroller.Pin](https://docs.python.org/3/library/microcontroller.html#microcontroller.Pin)) – Chip select pin
• **reset** ([microcontroller.Pin](https://docs.python.org/3/library/microcontroller.html#microcontroller.Pin)) – Reset pin. When None only software reset can be used
• **baudrate** ([int](https://docs.python.org/3/library/functions.html#int)) – Maximum baudrate in Hz for the display on the bus
• **polarity** ([int](https://docs.python.org/3/library/functions.html#int)) – the base state of the clock line (0 or 1)
• **phase** ([int](https://docs.python.org/3/library/functions.html#int)) – the edge of the clock that data is captured. First (0) or second (1). Rising or falling depends on clock polarity.

```python
reset() → None
```
Performs a hardware reset via the reset pin. Raises an exception if called when no reset pin is available.

```python
send(command: int, data: circuitpython_typing.ReadableBuffer, *, toggle_every_byte: bool = False) → None
```
Sends the given command value followed by the full set of data. Display state, such as vertical scroll, set via `send` may or may not be reset once the code is done.

```python
class displayio.Group(*, scale: int = 1, x: int = 0, y: int = 0)
```
Manage a group of sprites and groups and how they are inter-related.

Create a Group of a given size and scale. Scale is in one dimension. For example, scale=2 leads to a layer’s pixel being 2x2 pixels when in the group.

**Parameters**

• **scale** ([int](https://docs.python.org/3/library/functions.html#int)) – Scale of layer pixels in one dimension.
• **x** ([int](https://docs.python.org/3/library/functions.html#int)) – Initial x position within the parent.
• **y** ([int](https://docs.python.org/3/library/functions.html#int)) – Initial y position within the parent.

```python
hidden :bool
```
True when the Group and all of it’s layers are not visible. When False, the Group’s layers are visible if they haven’t been hidden.

```python
class :int
```
Scales each pixel within the Group in both directions. For example, when scale=2 each pixel will be represented by 2x2 pixels.

```python
x :int
```
X position of the Group in the parent.

```python
y :int
```
Y position of the Group in the parent.

```python
append(layer: Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]) → None
```
Append a layer to the group. It will be drawn above other layers.

```python
insert(index: int, layer: Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]) → None
```
Insert a layer into the group.

```python
index(index: int) → int
```
Returns the index of the first copy of layer. Raises ValueError if not found.

```python
pop(i: int = -1) → Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]
```
Remove the ith item and return it.

```python
remove(layer: Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]) → None
```
Remove the first copy of layer. Raises ValueError if it is not present.
__bool__() → bool

__len__() → int
   Returns the number of layers in a Group

__getitem__(index: int) → Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]
   Returns the value at the given index.
   This allows you to:
   ```
   print(group[0])
   ```

__setitem__(index: int, value: Union[vectorio.Circle, vectorio.Rectangle, vectorio.Polygon, Group, TileGrid]) → None
   Sets the value at the given index.
   This allows you to:
   ```
   group[0] = sprite
   ```

__delitem__(index: int) → None
   Deletes the value at the given index.
   This allows you to:
   ```
   del group[0]
   ```

sort(key: function, reverse: bool) → None
   Sort the members of the group.

class displayio.I2CDisplay(i2c_bus: busio.I2C, *, device_address: int, reset: Optional[microcontroller.Pin] = None)
   Manage updating a display over I2C in the background while Python code runs. It doesn’t handle display initial-
   ization.

Create a I2CDisplay object associated with the given I2C bus and reset pin.

The I2C bus and pins are then in use by the display until displayio.release_displays() is called even after a
 reload. (It does this so CircuitPython can use the display after your code is done.) So, the first time you initialize
a display bus in code.py you should call displayio.release_displays() first, otherwise it will error after
the first code.py run.

   Parameters

   • i2c_bus (busio.I2C) – The I2C bus that make up the clock and data lines
   • device_address (int) – The I2C address of the device
   • reset (microcontroller.Pin) – Reset pin. When None only software reset can be used

reset() → None
   Performs a hardware reset via the reset pin. Raises an exception if called when no reset pin is available.

send(command: int, data: circuitpython_typing.ReadableBuffer) → None
   Sends the given command value followed by the full set of data. Display state, such as vertical scroll, set
via send may or may not be reset once the code is done.
class displayio.OnDiskBitmap(file: Union[str, BinaryIO])

Loads values straight from disk. This minimizes memory use but can lead to much slower pixel load times. These load times may result in frame tearing where only part of the image is visible.

It’s easiest to use on a board with a built-in display such as the Hallowing M0 Express.

```python
import board
import displayio
import time
import pulseio

board.DISPLAY.brightness = 0
splash = displayio.Group()
board.DISPLAY.show(splash)

odb = displayio.OnDiskBitmap('/sample.bmp')
face = displayio.TileGrid(odb, pixel_shader=odb.pixel_shader)
splash.append(face)

# Wait for the image to load.
board.DISPLAY.refresh(target_frames_per_second=60)

# Fade up the backlight
for i in range(100):
    board.DISPLAY.brightness = 0.01 * i
    time.sleep(0.05)

# Wait forever
while True:
    pass
```

Create an OnDiskBitmap object with the given file.

**Parameters**

- `file` (file) – The name of the bitmap file. For backwards compatibility, a file opened in binary mode may also be passed.

Older versions of CircuitPython required a file opened in binary mode. CircuitPython 7.0 modified OnDiskBitmap so that it takes a filename instead, and opens the file internally. A future version of CircuitPython will remove the ability to pass in an opened file.

- `width` (int) – Width of the bitmap. (read only)
- `height` (int) – Height of the bitmap. (read only)

- `pixel_shader` :Union[ColorConverter, Palette]

  The image’s pixel_shader. The type depends on the underlying bitmap’s structure. The pixel shader can be modified (e.g., to set the transparent pixel or, for palette shaded images, to update the palette.)

class displayio.Palette(color_count: int)

Map a pixel palette_index to a full color. Colors are transformed to the display’s format internally to save memory.

Create a Palette object to store a set number of colors.

**Parameters**

- `color_count` (int) – The number of colors in the Palette
__bool__() → bool

__len__() → int

Returns the number of colors in a Palette

g__getitem__(index: int) → Optional[int]

Return the pixel color at the given index as an integer.

g__setitem__(index: int, value: Union[int, circuitpython_typing.ReadableBuffer, Tuple[int, int, int]]) → None

Sets the pixel color at the given index. The index should be an integer in the range 0 to color_count-1.

The value argument represents a color, and can be from 0x000000 to 0xFFFFFF (to represent an RGB value). Value can be an int, bytes (3 bytes (RGB) or 4 bytes (RGB + pad byte)), bytearray, or a tuple or list of 3 integers.

This allows you to:

```python
palette[0] = 0xFFFFFF  # set using an integer
palette[1] = b'xff\xff\x00'  # set using 3 bytes
palette[2] = b'xff\xff\x00\x00'  # set using 4 bytes
palette[3] = bytearray(b'\x00\x00\xff')  # set using a bytearray of 3 or 4 bytes
palette[4] = (10, 20, 30)  # set using a tuple of 3 integers
```

make_transparent(palette_index: int) → None

make_opaque(palette_index: int) → None

is_transparent(palette_index: int) → bool

Returns True if the palette index is transparent. Returns False if opaque.

class displayio.Shape(width: int, height: int, *, mirror_x: bool = False, mirror_y: bool = False)

Represents a shape made by defining boundaries that may be mirrored.

Create a Shape object with the given fixed size. Each pixel is one bit and is stored by the column boundaries of the shape on each row. Each row’s boundary defaults to the full row.

Parameters

- **width** (int) – The number of pixels wide
- **height** (int) – The number of pixels high
- **mirror_x** (bool) – When true the left boundary is mirrored to the right.
- **mirror_y** (bool) – When true the top boundary is mirrored to the bottom.

set_boundary(y: int, start_x: int, end_x: int) → None

Loads pre-packed data into the given row.

class displayio.TileGrid(bitmap: Union[Bitmap, OnDiskBitmap, Shape], *, pixel_shader: Union[ColorConverter, Palette], width: int = 1, height: int = 1, tile_width: Optional[int] = None, tile_height: Optional[int] = None, default_tile: int = 0, x: int = 0, y: int = 0)

A grid of tiles sourced out of one bitmap

Position a grid of tiles sourced from a bitmap and pixel_shader combination. Multiple grids can share bitmaps and pixel shaders.

A single tile grid is also known as a Sprite.
Create a TileGrid object. The bitmap is source for 2d pixels. The pixel_shader is used to convert the value and its location to a display native pixel color. This may be a simple color palette lookup, a gradient, a pattern or a color transformer.

To save RAM usage, tile values are only allowed in the range from 0 to 255 inclusive (single byte values). tile_width and tile_height match the height of the bitmap by default.

**Parameters**

- **bitmap** (*Bitmap, OnDiskBitmap, Shape*) – The bitmap storing one or more tiles.
- **pixel_shader** (*ColorConverter, Palette*) – The pixel shader that produces colors from values
- **width** (*int*) – Width of the grid in tiles.
- **height** (*int*) – Height of the grid in tiles.
- **tile_width** (*int*) – Width of a single tile in pixels. Defaults to the full Bitmap and must evenly divide into the Bitmap’s dimensions.
- **tile_height** (*int*) – Height of a single tile in pixels. Defaults to the full Bitmap and must evenly divide into the Bitmap’s dimensions.
- **default_tile** (*int*) – Default tile index to show.
- **x** (*int*) – Initial x position of the left edge within the parent.
- **y** (*int*) – Initial y position of the top edge within the parent.

**hidden** : *bool*

True when the TileGrid is hidden. This may be False even when a part of a hidden Group.

**x** : *int*

X position of the left edge in the parent.

**y** : *int*

Y position of the top edge in the parent.

**width** : *int*

Width of the tilegrid in tiles.

**height** : *int*

Height of the tilegrid in tiles.

**tile_width** : *int*

Width of a single tile in pixels.

**tile_height** : *int*

Height of a single tile in pixels.

**flip_x** : *bool*

If true, the left edge rendered will be the right edge of the right-most tile.

**flip_y** : *bool*

If true, the top edge rendered will be the bottom edge of the bottom-most tile.

**transpose_xy** : *bool*

If true, the TileGrid’s axis will be swapped. When combined with mirroring, any 90 degree rotation can be achieved along with the corresponding mirrored version.
pixel_shader : Union[ColorConverter, Palette]
The pixel shader of the tilegrid.

bitmap : Union[Bitmap, OnDiskBitmap, Shape]
The bitmap of the tilegrid.

contains(touch_tuple: tuple) → bool
Returns True if the first two values in touch_tuple represent an x,y coordinate inside the tilegrid rectangle bounds.

__getitem__(index: Union[Tuple[int, int], int]) → int
Returns the tile index at the given index. The index can either be an x,y tuple or an int equal to \( y \times width + x \).

This allows you to:

```
print(grid[0])
```

__setitem__(index: Union[Tuple[int, int], int], value: int) → None
Sets the tile index at the given index. The index can either be an x,y tuple or an int equal to \( y \times width + x \).

This allows you to:

```
grid[0] = 10
```

or:

```
grid[0,0] = 10
```

dotenv – Functions to manage environment variables from a .env file.

A subset of the CPython dotenv library. It does not support variables or double quotes.

Keys and values may be put in single quotes. \ and ' are escaped by \ in single quotes. Newlines can occur in quotes for multiline values. Comments start with # and apply for the rest of the line. A # immediately following an = is part of the value, not the start of a comment, and a # embedded in a value without whitespace will be part of that value. This corresponds to how assignments and comments work in most Unix shells.

File format example:

```
key=value
    key2 = value2
'value with spaces'
# comment
key4 = value3 # comment 2
'value with spaces'
key5=value4
key=value5 # overrides the first one
multiline = 'hello
world
how are you?'
# The #’s below will be included in the value. They do not start a comment.
key6=#value
key7=abc#def
```
dotenv.get_key(dotenv_path: str, key_to_get: str) → Optional[str]

Get the value for the given key from the given .env file. If the key occurs multiple times in the file, then the last value will be returned.

Returns None if the key isn’t found or doesn’t have a value.

dotenv.load_dotenv() → None

Does nothing in CircuitPython because os.getenv will automatically read .env when available.

Present in CircuitPython so CPython-compatible code can use it without error.

dualbank – DUALBANK Module

The dualbank module adds ability to update and switch between the two app partitions.

There are two identical partitions, these contain different firmware versions. Having two partitions enables rollback functionality.

The two partitions are defined as boot partition and next-update partition. Calling dualbank.flash() writes the next-update partition.

After the next-update partition is written a validation check is performed and on a successful validation this partition is set as the boot partition. On next reset, firmware will be loaded from this partition.

Here is the sequence of commands to follow:

```python
import dualbank
dualbank.flash(buffer, offset)
dualbank.switch()
```

dualbank.flash(buffer: circuitpython_typing.ReadableBuffer, offset: int = 0) → None

Writes one of two app partitions at the given offset.

This can be called multiple times when flashing the firmware in small chunks.

dualbank.switch() → None

Switches the boot partition.

On next reset, firmware will be loaded from the partition just switched over to.

esp32_camera – Wrapper for the esp32_camera library

This library enables access to any camera sensor supported by the library, including OV5640 and OV2640.

See also:

Non-Espressif microcontrollers use the imagecapture module together with wrapper libraries such as adafruit_ov5640.

class esp32_camera.GrabMode

Controls when a new frame is grabbed.

WHEN_EMPTY :GrabMode

Fills buffers when they are empty. Less resources but first fb_count frames might be old

LATEST :GrabMode

Except when 1 frame buffer is used, queue will always contain the last fb_count frames
class esp32_camera.PixelFormat
    Format of data in the captured frames
    RGB565 :PixelFormat
        A 16-bit format with 5 bits of Red and Blue and 6 bits of Green
    GRAYSCALE :PixelFormat
        An 8-bit format with 8-bits of luminance
    JPEG :PixelFormat
        A compressed format

class esp32_camera.FrameSize
    The pixel size of the captured frames
    R96X96 :FrameSize
        96x96
    QQVGA :FrameSize
        160x120
    QCIF :FrameSize
        176x144
    HQVGA :FrameSize
        240x176
    R240X240 :FrameSize
        240x240
    QVGA :FrameSize
        320x240
    CIF :FrameSize
        400x296
    HVGA :FrameSize
        480x320
    VGA :FrameSize
        640x480
    SVGA :FrameSize
        800x600
    XGA :FrameSize
        1024x768
    HD :FrameSize
        1280x720
    SXGA :FrameSize
        1280x1024
    UXGA :FrameSize
        1600x1200
    FHD :FrameSize
        1920x1080
The maximum amount of gain applied to raw sensor data. Higher values are useful in darker conditions, but increase image noise.

GAIN_2X : GainCeiling
GAIN_4X : GainCeiling
GAIN_8X : GainCeiling
GAIN_16X : GainCeiling
GAIN_32X : GainCeiling
GAIN_64X : GainCeiling
GAIN_128X : GainCeiling

Configure and initialize a camera with the given properties

This driver requires that the CIRCUITPY_RESERVED_PSRAM in /.env be large enough to hold the camera framebuffer(s). Generally, boards with built-in cameras will have a default setting that is large enough. If the constructor raises a MemoryError or an IDFError, this probably indicates the setting is too small and should be increased.

Important: Not all supported sensors have all of the properties listed below. For instance, the OV5640 supports denoise, but the OV2640 does not. The underlying esp32-camera library does not provide a reliable API.
to check which settings are supported. CircuitPython makes a best effort to determine when an unsupported property is set and will raise an exception in that case.

### Parameters

- **data_pins** – The 8 data data_pins used for image data transfer from the camera module, least significant bit first
- **pixel_clock_pin** – The pixel clock output from the camera module
- **vsync_pin** – The vertical sync pulse output from the camera module
- **href_pin** – The horizontal reference output from the camera module
- **i2c** – The I2C bus connected to the camera module
- **external_clock_pin** – The pin on which to generate the external clock
- **external_clock_frequency** – The frequency generated on the external clock pin
- **powerdown_pin** – The powerdown input to the camera module
- **reset_pin** – The reset input to the camera module
- **pixel_format** – The pixel format of the captured image
- **frame_size** – The size of captured image
- **jpeg_quality** – For `PixelFormat.JPEG`, the quality. Higher numbers increase quality. If the quality is too high, the JPEG data will be larger than the available buffer size and the image will be unusable or truncated. The exact range of appropriate values depends on the sensor and must be determined empirically.
- **framebuffer_count** – The number of framebuffers (1 for single-buffered and 2 for double-buffered)
- **grab_mode** – When to grab a new frame

#### frame_available :bool

True if a frame is available, False otherwise

#### pixel_format :PixelFormat

The pixel format of captured frames

#### frame_size :FrameSize

The size of captured frames

#### contrast :int

The sensor contrast. Positive values increase contrast, negative values lower it. The total range is device-specific but is often from -2 to +2 inclusive.

#### brightness :int

The sensor brightness. Positive values increase brightness, negative values lower it. The total range is device-specific but is often from -2 to +2 inclusive.

#### saturation :int

The sensor saturation. Positive values increase saturation (more vibrant colors), negative values lower it (more muted colors). The total range is device-specific but the value is often from -2 to +2 inclusive.
sharpness :int
The sensor sharpness. Positive values increase sharpness (more defined edges), negative values lower it (softer edges). The total range is device-specific but the value is often from -2 to +2 inclusive.

denoise :int
The sensor ‘denoise’ setting. Any camera sensor has inherent ‘noise’, especially in low brightness environments. Software algorithms can decrease noise at the expense of fine detail. A larger value increases the amount of software noise removal. The total range is device-specific but the value is often from 0 to 10.

gain_ceiling :GainCeiling
The sensor ‘gain ceiling’ setting. “Gain” is an analog multiplier applied to the raw sensor data. The ‘ceiling’ is the maximum gain value that the sensor will use. A higher gain means that the sensor has a greater response to light, but also makes sensor noise more visible.

quality :int
The ‘quality’ setting when capturing JPEG images. This is similar to the quality setting when exporting a jpeg image from photo editing software. Typical values range from 5 to 40, with higher numbers leading to larger image sizes and better overall image quality. However, when the quality is set to a high number, the total size of the JPEG data can exceed the size of an internal buffer, causing image capture to fail.

colorbar :bool
When True, a test pattern image is captured and the real sensor data is not used.

whitebal :bool
When True, the camera attempts to automatically control white balance. When False, the wb_mode setting is used instead.

gain_ctrl :bool
When True, the camera attempts to automatically control the sensor gain, up to the value in the gain_ceiling property. When False, the agc_gain setting is used instead.

exposure_ctrl :bool
When True the camera attempts to automatically control the exposure. When False, the aec_value setting is used instead.

hmirror :bool
When True the camera image is mirrored left-to-right

vflip :bool
When True the camera image is flipped top-to-bottom

aec2 :bool
When True the sensor’s “night mode” is enabled, extending the range of automatic gain control.

awb_gain :bool
Access the awb_gain property of the camera sensor

agc_gain :int
Access the gain level of the sensor. Higher values produce brighter images. Typical settings range from 0 to 30.

aec_value :int
Access the exposure value of the camera. Higher values produce brighter images. Typical settings range from 0 to 1200.

special_effect :int
Enable a “special effect”. Zero is no special effect. On OV5640, special effects range from 0 to 6 inclusive and select various color modes.
wb_mode : int
The white balance mode. 0 is automatic white balance. Typical values range from 0 to 4 inclusive.

ae_level : int
The exposure offset for automatic exposure. Typical values range from -2 to +2.

dcw : bool
When True an advanced white balance mode is selected.

bpc : bool
When True, “black point compensation” is enabled. This can make black parts of the image darker.

wpc : bool
When True, “white point compensation” is enabled. This can make white parts of the image whiter.

raw_gma : bool
When True, raw gamma mode is enabled.

lenc : bool
Enable “lens correction”. This can help compensate for light fall-off at the edge of the sensor area.

max_frame_size : FrameSize
The maximum frame size that can be captured

address : int
The I2C (SCCB) address of the sensor

sensor_name : str
The name of the sensor

supports_jpeg : bool
True if the sensor can capture images in JPEG format

height : int
The height of the image being captured

width : int
The width of the image being captured

grab_mode : GrabMode
The grab mode of the camera

framebuffer_count : int
True if double buffering is used

deinit() → None
Deinitialises the camera and releases all memory resources for reuse.

__enter__() → Camera
No-op used by Context Managers.

__exit__() → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.
**take** (timeout: Optional[float] = 0.25) \rightarrow Optional[displayio.Bitmap | ReadableBuffer]

Record a frame. Wait up to ‘timeout’ seconds for a frame to be captured.

In the case of timeout, None is returned. If pixel_format is PixelFormat.JPEG, the returned value is a read-only memoryview. Otherwise, the returned value is a read-only displayio.Bitmap.

**reconfigure** (frame_size: Optional[FrameSize] = None, pixel_format: Optional[PixelFormat] = None, grab_mode: Optional[GrabMode] = None, framebuffer_count: Optional[int] = None) \rightarrow None

Change multiple related camera settings simultaneously.

Because these settings interact in complex ways, and take longer than the other properties to set, they are set together in a single function call.

If an argument is unspecified or None, then the setting is unchanged.

**espidf**

Direct access to a few ESP-IDF details. This module should not include any functionality that could be implemented by other frameworks. It should only include ESP-IDF specific things.

**espidf.** heap_caps_get_total_size() \rightarrow int

Return the total size of the ESP-IDF, which includes the CircuitPython heap.

**espidf.** heap_caps_get_free_size() \rightarrow int

Return total free memory in the ESP-IDF heap.

**espidf.** heap_caps_get_largest_free_block() \rightarrow int

Return the size of largest free memory block in the ESP-IDF heap.

**espidf.** erase_nvs() \rightarrow None

Erase all data in the non-volatile storage (nvs), including data stored by with microcontroller.nvm

This is necessary when upgrading from CircuitPython 6.3.0 or earlier to CircuitPython 7.0.0, because the layout of data in nvs has changed. The old data will be lost when you perform this operation.

**exception** espidf.MemoryError

Bases: MemoryError

Raised when an ESP IDF memory allocation fails.

Initialize self. See help(type(self)) for accurate signature.

**espidf.** get_total_psram() \rightarrow int

Returns the number of bytes of psram detected, or 0 if psram is not present or not configured

**espidf.** get_reserved_psram() \rightarrow int

Returns number of bytes of psram reserved for use by esp-idf, either a board-specific default value or the value defined in /.env.
floppyio – Read flux transition information into the buffer.

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get_glyph(codepoint: int) → Optional[Glyph]
Retrieve the Glyph for a given code point
If the code point is not present in the font, None is returned.

class fontio.BuiltinFont
A font built into CircuitPython
Creation not supported. Available fonts are defined when CircuitPython is built. See the Adafruit_CircuitPython_Bitmap_Font library for dynamically loaded fonts.

bitmap : displayio.Bitmap
Bitmap containing all font glyphs starting with ASCII and followed by unicode. Use get_glyph in most cases. This is useful for use with displayio.TileGrid and terminalio.Terminal.

get_bounding_box() → Tuple[int, int]
Returns the maximum bounds of all glyphs in the font in a tuple of two values: width, height.

get_glyph(codepoint: int) → Glyph
Returns a fontio.Glyph for the given codepoint or None if no glyph is available.

Storage of glyph info
Named tuple used to capture a single glyph and its attributes.

Parameters
- bitmap – the bitmap including the glyph
- tile_index – the tile index within the bitmap
- width – the width of the glyph’s bitmap
- height – the height of the glyph’s bitmap
- dx – x adjustment to the bitmap’s position
- dy – y adjustment to the bitmap’s position
- shift_x – the x difference to the next glyph
- shift_y – the y difference to the next glyph

framebufferio – Native framebuffer display driving

The framebufferio module contains classes to manage display output including synchronizing with refresh rates and partial updating. It is used in conjunction with classes from displayio to actually place items on the display; and classes like RGBMatrix to actually drive the display.

class framebufferio.FramebufferDisplay(framebuffer: circuitpython_typing.FrameBuffer, * , rotation: int = 0, auto_refresh: bool = True)
Manage updating a display with framebuffer in RAM
This initializes a display and connects it into CircuitPython. Unlike other objects in CircuitPython, Display objects live until displayio.release_displays() is called. This is done so that CircuitPython can use the display itself.
Create a Display object with the given framebuffer (a buffer, array, ulab.array, etc)

Parameters
• **framebuffer** (*FrameBuffer*) – The framebuffer that the display is connected to

• **auto_refresh** (*bool*) – Automatically refresh the screen

• **rotation** (*int*) – The rotation of the display in degrees clockwise. Must be in 90 degree increments (0, 90, 180, 270)

```python
auto_refresh : bool
    True when the display is refreshed automatically.
```

```python
brightness : float
    The brightness of the display as a float. 0.0 is off and 1.0 is full brightness.
```

```python
width : int
    Gets the width of the framebuffer
```

```python
height : int
    Gets the height of the framebuffer
```

```python
rotation : int
    The rotation of the display as an int in degrees.
```

```python
framebuffer : circuitpython_typing.FrameBuffer
    The framebuffer being used by the display
```

```python
root_group : displayio.Group
    The root group on the display.
```

```python
show(group: displayio.Group) → None
    Switches to displaying the given group of layers. When group is None, the default CircuitPython terminal will be shown.

    Parameters
    group (*Group*) – The group to show.
```

```python
refresh(*, target_frames_per_second: int = 60, minimum_frames_per_second: int = 1) → bool
    When auto refresh is off, waits for the target frame rate and then refreshes the display, returning True. If the call has taken too long since the last refresh call for the given target frame rate, then the refresh returns False immediately without updating the screen to hopefully help getting caught up.

    If the time since the last successful refresh is below the minimum frame rate, then an exception will be raised. Set minimum_frames_per_second to 0 to disable.

    When auto refresh is on, updates the display immediately. (The display will also update without calls to this.)

    Parameters
    • target_frames_per_second (*int*) – How many times a second *refresh* should be called and the screen updated.

    • minimum_frames_per_second (*int*) – The minimum number of times the screen should be updated per second.
```

```python
fill_row(y: int, buffer: circuitpython_typing.WriteableBuffer) → circuitpython_typing.WriteableBuffer
    Extract the pixels from a single row

    Parameters
    • y (*int*) – The top edge of the area

    • buffer (WriteableBuffer) – The buffer in which to place the pixel data
```
**frequencyio – Support for frequency based protocols**

**Warning:** This module is not available in SAMD21 builds. See the Module Support Matrix - Which Modules Are Available on Which Boards for more info.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See Lifetime and Context Managers for more info.

For example:

```python
import time
import frequencyio
import board

frequency = frequencyio.FrequencyIn(board.D11)
frequency.capture_period = 15
time.sleep(0.1)
```

This example will initialize the the device, set `capture_period`, and then sleep 0.1 seconds. CircuitPython will automatically turn off FrequencyIn capture when it resets all hardware after program completion. Use `deinit()` or a `with` statement to do it yourself.

**class** frequencyio.FrequencyIn(*pin: microcontroller.Pin, capture_period: int = 10*)

Read a frequency signal

FrequencyIn is used to measure the frequency, in hertz, of a digital signal on an incoming pin. Accuracy has shown to be within 10%, if not better. It is recommended to utilize an average of multiple samples to smooth out readings.

Frequencies below 1KHz are not currently detectable.

FrequencyIn will not determine pulse width (use `PulseIn`).

Create a FrequencyIn object associated with the given pin.

**Parameters**

- **pin** *(Pin)* – Pin to read frequency from.
- **capture_period** *(int)* – Keyword argument to set the measurement period, in milliseconds. Default is 10ms; range is 1ms - 500ms.

Read the incoming frequency from a pin:

```python
import frequencyio
import board

frequency = frequencyio.FrequencyIn(board.D11)

# Loop while printing the detected frequency
while True:
    print(frequency.value)
    # Optional clear() will reset the value
    # to zero. Without this, if the incoming
    # signal stops, the last reading will remain
```

(continues on next page)
# as the value.
  frequency.clear()

capture_period : int
  The capture measurement period. Lower incoming frequencies will be measured more accurately with
  longer capture periods. Higher frequencies are more accurate with shorter capture periods.

  **Note:** When setting a new capture_period, all previous capture information is cleared with a call to
clear().

definit() → None
  Deinitialises the FrequencyIn and releases any hardware resources for reuse.

__enter__() → FrequencyIn
  No-op used by Context Managers.

__exit__() → None
  Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for
  more info.

pause() → None
  Pause frequency capture.

resume() → None
  Resumes frequency capture.

clear() → None
  Clears the last detected frequency capture value.

__get__(index: int) → int
  Returns the value of the last frequency captured.

getpass – Getpass Module

This module provides a way to get input from user without echoing it.

  Prompt the user without echoing.

  **Parameters**

  • **prompt** (str) – The user is prompted using the string prompt, which defaults to
    'Password: '.

  • **stream** (io.FileIO) – The prompt is written to the file-like object stream if provided.
gifio – Access GIF-format images


Construct a GifWriter object

Parameters

• file – Either a file open in bytes mode, or the name of a file to open in bytes mode.
• width – The width of the image. All frames must have the same width.
• height – The height of the image. All frames must have the same height.
• colorspace – The colorspace of the image. All frames must have the same colorspace. The supported colorspaces are RGB565, BGR565, RGB565_SWAPPED, BGR565_SWAPPED, and L8 (greyscale)
• loop – If True, the GIF is marked for looping playback
• dither – If True, and the image is in color, a simple ordered dither is applied.

__enter__() → GifWriter

No-op used by Context Managers.

__exit__() → None

Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

definit() → None

Close the underlying file.

add_frame(bitmap: circuitpython_typing.ReadableBuffer, delay: float = 0.1) → None

Add a frame to the GIF.

Parameters

• bitmap – The frame data
• delay – The frame delay in seconds. The GIF format rounds this to the nearest 1/100 second, and the largest permitted value is 655 seconds.

gnss – Global Navigation Satellite System

The gnss module contains classes to control the GNSS and acquire positioning information.

class gnss.GNSS(system: Union[SatelliteSystem, List[SatelliteSystem]])

Get updated positioning information from Global Navigation Satellite System (GNSS)

Usage:

```python
import gnss
import time

nav = gnss.GNSS([gnss.SatelliteSystem.GPS, gnss.SatelliteSystem.GLONASS])
last_print = time.monotonic()
while True:
    nav.update()
```

(continues on next page)
current = time.monotonic()
if current - last_print >= 1.0:
    last_print = current
if nav.fix is gnss.PositionFix.INVALID:
    print("Waiting for fix...")
    continue
print("Latitude: {0:.6f} degrees".format(nav.latitude))
print("Longitude: {0:.6f} degrees".format(nav.longitude))

Turn on the GNSS.

Parameters

    system – satellite system to use

latitude :float
    Latitude of current position in degrees (float).

longitude :float
    Longitude of current position in degrees (float).

altitude :float
    Altitude of current position in meters (float).

timestamp :time.struct_time
    Time when the position data was updated.

fix :PositionFix
    Fix mode.

deinit() → None
    Turn off the GNSS.

update() → None
    Update GNSS positioning information.

class gnss.PositionFix
    Position fix mode
    Enum-like class to define the position fix mode.

    INVALID :PositionFix
        No measurement.

    FIX_2D :PositionFix
        2D fix.

    FIX_3D :PositionFix
        3D fix.

class gnss.SatelliteSystem
    Satellite system type
    Enum-like class to define the satellite system type.

    GPS :SatelliteSystem
        Global Positioning System.
GLONASS : Satellite System
GLObal NAvigation Satellite System.

SBAS : Satellite System
Satellite Based Augmentation System.

QZSS_L1CA : Satellite System
Quasi-Zenith Satellite System L1C/A.

QZSS_L1S : Satellite System
Quasi-Zenith Satellite System L1S.

**hashlib – Hashing related functions**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: `hashlib`

```python
hashlib.new(name: str, data: bytes = b'') → Hash
```

**Returns**

A Hash object setup for the named algorithm. Raises ValueError when the named algorithm is unsupported.

**Returns**

A hash object for the given algorithm

**Return type**

`hashlib.Hash`

```python
class hashlib.Hash

In progress hash algorithm. This object is always created by a `hashlib.new()`. It has no user-visible constructor.

```python
digest_size : int

Digest size in bytes

```python
update(data: circuitpython_typing.ReadableBuffer) → None

Update the hash with the given bytes.

**Parameters**

data (ReadableBuffer) – Update the hash from data in this buffer

```python
digest() → bytes

Returns the current digest as bytes() with a length of `hashlib.Hash.digest_size`.

**i2ctarget – Two wire serial protocol target**

The `i2ctarget` module contains classes to support an I2C target.

Example emulating a target with 2 addresses (read and write):

```python
import board
from i2ctarget import I2CTarget

regs = [0] * 16
index = 0
```

(continues on next page)
with I2CTarget(board.SCL, board.SDA, (0x40, 0x41)) as device:
    while True:
        r = device.request()
        if not r:
            # Maybe do some housekeeping
            continue
        with r:
            # Closes the transfer if necessary by sending a NACK or feeding dummy.
            ...bytes
            if r.address == 0x40:
                if not r.is_read:  # Main write which is Selected read
                    b = r.read(1)
                    if not b or b[0] > 15:
                        break
                    index = b[0]
                    b = r.read(1)
                    if b:
                        regs[index] = b[0]
                elif r.is_restart:  # Combined transfer: This is the Main read message
                    n = r.write(bytes([regs[index]]))
            ...manager (r.close())
            elif r.address == 0x41:
                if not r.is_read:
                    b = r.read(1)
                    if b and b[0] == 0xde:
                        # do something
                        pass

This example sets up an I2C device that can be accessed from Linux like this:

```bash
$ i2cget -y 1 0x40 0x01
0x00
$ i2cset -y 1 0x40 0x01 0xaa
$ i2cget -y 1 0x40 0x01
0xaa
```

**Warning:** I2CTarget makes use of clock stretching in order to slow down the host. Make sure the I2C host supports this.

Raspberry Pi in particular does not support this with its I2C hw block. This can be worked around by using the `i2c-gpio` bit banging driver. Since the RPi firmware uses the hw i2c, it’s not possible to emulate a HAT eeprom.

class i2ctarget.I2CTarget(scl: microcontroller.Pin, sda: microcontroller.Pin, addresses: Sequence[int], smbus: bool = False)

Two wire serial protocol target

I2C is a two-wire protocol for communicating between devices. This implements the target (peripheral, sensor, secondary) side.
Parameters

• **scl** *(Pin)* – The clock pin
• **sda** *(Pin)* – The data pin
• **addresses** *(list[int]*) – The I2C addresses to respond to (how many is hardware dependent).
• **smbus** *(bool)* – Use SMBUS timings if the hardware supports it

```
definit() -> None
```

Releases control of the underlying hardware so other classes can use it.

```
__enter__() -> I2CTarget
```

No-op used in Context Managers.

```
__exit__() -> None
```

Automatically deinitializes the hardware on context exit. See *Lifetime and ContextManagers* for more info.

```
request(*, timeout: float = -1) -> I2CTargetRequest
```

Wait for an I2C request.

Parameters

```
timeout (float) – Timeout in seconds. Zero means wait forever, a negative value means check once
```

Returns

I2CTargetRequest or None if timeout=-1 and there’s no request

Return type

I2CTargetRequest

class i2ctarget.I2CTargetRequest(target: I2CTarget, address: int, is_read: bool, is_restart: bool)

Information about an I2C transfer request This cannot be instantiated directly, but is returned by *I2CTarget. request(*)*. Parameters

• **target** – The I2CTarget object receiving this request
• **address** – I2C address
• **is_read** – True if the main target is requesting data
• **is_restart** – Repeated Start Condition

```
address :int
```

The I2C address of the request.

```
is_read :bool
```

The I2C main controller is reading from this target.

```
is_restart :bool
```

Is Repeated Start Condition.

```
__enter__() -> I2CTargetRequest
```

No-op used in Context Managers.

```
__exit__() -> None
```

Close the request.
**read**\( (n: \text{int} = -1, \text{ack: bool} = \text{True}) \rightarrow \text{bytearray} \)

Read data. If \text{ack}=\text{False}, the caller is responsible for calling \text{I2CTargetRequest.ack().}

**Parameters**

- \text{n} – Number of bytes to read (negative means all)
- \text{ack} – Whether or not to send an ACK after the \text{n}’th byte

**Returns**

Bytes read

**write**\( (\text{buffer: circuitpython_typing.ReadableBuffer}) \rightarrow \text{int} \)

Write the data contained in buffer.

**Parameters**

- \text{buffer (ReadableBuffer)} – Write out the data in this buffer

**Returns**

Number of bytes written

**ack**\( (\text{ack: bool} = \text{True}) \rightarrow \text{None} \)

Acknowledge or Not Acknowledge last byte received. Use together with \text{I2CTargetRequest.read()} \text{ack=False}.

**Parameters**

- \text{ack} – Whether to send an ACK or NACK

---

**imagecapture** – Support for “Parallel capture” interfaces

See also:

Espressif microcontrollers use the \text{esp32_camera} module together.


Capture image frames from a camera with parallel data interface

Create a parallel image capture object

This object is usually used with a camera-specific wrapper library such as \text{adafruit_ov5640}.

**Parameters**

- \text{data_pins (List[microcontroller.Pin])} – The data pins.
- \text{clock (microcontroller.Pin)} – The pixel clock input.
- \text{vsync (microcontroller.Pin)} – The vertical sync input, which has a negative-going pulse at the beginning of each frame.
- \text{href (microcontroller.Pin)} – The horizontal reference input, which is high whenever the camera is transmitting valid pixel information.

**capture**\( (\text{buffer: circuitpython_typing.WriteableBuffer}) \rightarrow \text{circuitpython_typing.WriteableBuffer} \)

Capture a single frame into the given buffer.

This will stop a continuous-mode capture, if one is in progress.
**continuous_capture_start** *(buffer1: circuitpython_typing.WriteableBuffer, buffer2: circuitpython_typing.WriteableBuffer, /) → None*

Begin capturing into the given buffers in the background.

Call **continuous_capture_get_frame** to get the next available frame, and **continuous_capture_stop** to stop capturing.

Until **continuous_capture_stop** (or **deinit**) is called, the ParallelImageCapture object keeps references to buffer1 and buffer2, so the objects will not be garbage collected.

**continuous_capture_get_frame** () → circuitpython_typing.WriteableBuffer

Return the next available frame, one of the two buffers passed to **continuous_capture_start**

**continuous_capture_stop** () → None

Stop continuous capture.

Calling this method also causes the object to release its references to the buffers passed to **continuous_capture_start**, potentially allowing the objects to be garbage collected.

**deinit** () → None

Deinitialize this instance

**__enter__** () → ParallelImageCapture

No-op used in Context Managers.

**__exit__** () → None

Automatically deinitializes the hardware on context exit. See *Lifetime and Context Managers* for more info.

**ipaddress**

The **ipaddress** module provides types for IP addresses. It is a subset of CPython’s ipaddress module.

**ipaddress.ip_address** *(obj: Union[int, str]) → IPv4Address*

Return a corresponding IP address object or raise ValueError if not possible.

**class ipaddress.IPv4Address** *(address: Union[int, str, bytes]*)

Encapsulates an IPv4 address.

Create a new IPv4Address object encapsulating the address value.

The value itself can either be bytes or a string formatted address.

**packed :bytes**

The bytes that make up the address (read-only).

**version :int**

4 for IPv4, 6 for IPv6

**__eq__**(other: object) → bool

Two Address objects are equal if their addresses and address types are equal.

**__hash__**() → int

Returns a hash for the IPv4Address data.
**is31fl3741** – Creates an in-memory framebuffer for a IS31FL3741 device.

```python
class is31fl3741.IS31FL3741_FrameBuffer(is31: IS31FL3741, width: int, height: int, mapping: Tuple[int, Ellipsis], *, framebuffer: Optional[circuitpython_typing.WriteableBuffer] = None, scale: bool = False, gamma: bool = False)
```

Create a IS31FL3741_FrameBuffer object with the given attributes.

The framebuffer is in “RGB888” format using 4 bytes per pixel. Bits 24-31 are ignored. The format is in RGB order.

If a framebuffer is not passed in, one is allocated and initialized to all black. In any case, the framebuffer can be retrieved by passing the Is31fl3741 object to memoryview().

A Is31fl3741 is often used in conjunction with a framebufferio.FramebufferDisplay.

**Parameters**

- **is31** (is31fl3741.IS31FL3741) – base IS31FL3741 instance to drive the framebuffer
- **width** (int) – width of the display
- **height** (int) – height of the display
- **mapping** (Tuple[int, ...]) – mapping of matrix locations to LEDs
- **framebuffer** (Optional[circuitpython_typing.WriteableBuffer]) – Optional buffer to hold the display
- **scale** (bool) – if True display is scaled down by 3 when displayed
- **gamma** (bool) – if True apply gamma correction to all LEDs

**brightness** : float

In the current implementation, 0.0 turns the display off entirely and any other value up to 1.0 turns the display on fully.

**width** : int

The width of the display, in pixels

**height** : int

The height of the display, in pixels

**deinit()** → None

Free the resources associated with this IS31FL3741 instance. After deinitialization, no further operations may be performed.

**refresh()** → None

Transmits the color data in the buffer to the pixels so that they are shown.

```python
class is31fl3741.IS31FL3741(i2c: busio.I2C, *, addr: int = 48)
```

Driver for an IS31FL3741 device.

Create a IS31FL3741 object with the given attributes.

Designed to work low level or passed to and object such as IS31FL3741_FrameBuffer.

**Parameters**

- **i2c** (I2C) – I2C bus the IS31FL3741 is on
- **addr** (int) – device address

---

1.8. Full Table of Contents
deinit() → None
Free the resources associated with this IS31FL3741 instance. After deinitialization, no further operations may be performed.

is31fl3741.reset(self) → None
Resets the IS31FL3741 chip.

is31fl3741.enable(self) → None
Enables the IS31FL3741 chip.

is31fl3741.set_global_current(self, current: int) → None
Sets the global current of the IS31FL3741 chip.

Parameters
  current (int) – global current value 0x00 to 0xFF

is31fl3741.set_led(self, led: int, value: int, page: int) → None
Resets the IS31FL3741 chip.

Parameters
  • led (int) – which LED to set
  • value (int) – value to set the LED to 0x00 to 0xFF
  • page (int) – page to write to 0 or 2. If the LED is a >= 180 the routine will automatically write to page 1 or 3 (instead of 0 or 2)

is31fl3741.write(mapping: Tuple[int, Ellipsis], buf: circuitpython_typing.ReadableBuffer) → None
Write buf out on the I2C bus to the IS31FL3741.

Parameters
  • mapping (~Tuple[int, ...]) – map the pixels in the buffer to the order addressed by the driver chip
  • buf (ReadableBuffer) – The bytes to clock out. No assumption is made about color order

kepad – Support for scanning keys and key matrices

The keypad module provides native support to scan sets of keys or buttons, connected independently to individual pins, connected to a shift register, or connected in a row-and-column matrix.

For more information about working with the keypad module in CircuitPython, see this Learn guide.

class keypad.Event(key_number: int = 0, pressed: bool = True, timestamp: Optional[int] = None)
A key transition event.

Create a key transition event, which reports a key-pressed or key-released transition.

Parameters
  • key_number (int) – The key number.
  • pressed (bool) – True if the key was pressed; False if it was released.
  • timestamp (int)– The time in milliseconds that the keypress occurred in the supervisor. ticks_ms time system. If specified as None, the current value of supervisorticks_ms is used.
key_number : int
The key number.

pressed : bool
True if the event represents a key down (pressed) transition. The opposite of released.

released : bool
True if the event represents a key up (released) transition. The opposite of pressed.

timestamp : int
The timestamp.

__eq__(other: object) → bool
Two Event objects are equal if their key_number and pressed/released values are equal. Note that this does not compare the event timestamps.

__hash__() → int
Returns a hash for the Event, so it can be used in dictionaries, etc..
Note that as events with different timestamps compare equal, they also hash to the same value.

class keypad.EventQueue
A queue of Event objects, filled by a keypad scanner such as Keys or KeyMatrix.
You cannot create an instance of EventQueue directly. Each scanner creates an instance when it is created.

overflowed : bool
True if an event could not be added to the event queue because it was full. (read-only) Set to False by clear().

get() → Optional[Event]
Return the next key transition event. Return None if no events are pending.
Note that the queue size is limited; see max_events in the constructor of a scanner such as Keys or KeyMatrix. If a new event arrives when the queue is full, the event is discarded, and overflowed is set to True.

Returns
The next queued key transition Event.

Return type
Optional[Event]

get_into(event: Event) → bool
Store the next key transition event in the supplied event, if available, and return True. If there are no queued events, do not touch event and return False.

The advantage of this method over get() is that it does not allocate storage. Instead you can reuse an existing Event object.

Note that the queue size is limited; see max_events in the constructor of a scanner such as Keys or KeyMatrix.

Returns
True if an event was available and stored, False if not.

Return type
bool
clear() → None
Clear any queued key transition events. Also sets overflowed to False.

__bool__() → bool
True if len() is greater than zero. This is an easy way to check if the queue is empty.

__len__() → int
Return the number of events currently in the queue. Used to implement len().

class keypad.KeyMatrix(row_pins: Sequence[microcontroller.Pin], column_pins: Sequence[microcontroller.Pin], columns_to_anodes: bool = True, interval: float = 0.02, max_events: int = 64)
Manage a 2D matrix of keys with row and column pins.
Create a Keys object that will scan the key matrix attached to the given row and column pins. There should not be any external pull-ups or pull-downs on the matrix: KeyMatrix enables internal pull-ups or pull-downs on the pins as necessary.
The keys are numbered sequentially from zero. A key number can be computed by row * len(column_pins) + column.
An EventQueue is created when this object is created and is available in the events attribute.

Parameters
• row_pins (Sequence[microcontroller.Pin]) – The pins attached to the rows.
• column_pins (Sequence[microcontroller.Pin]) – The pins attached to the columns.
• columns_to_anodes (bool) – Default True. If the matrix uses diodes, the diode anodes are typically connected to the column pins, and the cathodes should be connected to the row pins. If your diodes are reversed, set columns_to_anodes to False.
• interval (float) – Scan keys no more often than interval to allow for debouncing. interval is in float seconds. The default is 0.020 (20 msecs).
• max_events (int) – maximum size of events EventQueue: maximum number of key transition events that are saved. Must be >= 1. If a new event arrives when the queue is full, the oldest event is discarded.

key_count :int
The number of keys that are being scanned. (read-only)

events :EventQueue
The EventQueue associated with this Keys object. (read-only)

deinit() → None
Stop scanning and release the pins.

__enter__() → KeyMatrix
No-op used by Context Managers.

__exit__() → None
Automatically deinitializes when exiting a context. See Lifetime and ContextManagers for more info.

reset() → None
Reset the internal state of the scanner to assume that all keys are now released. Any key that is already pressed at the time of this call will therefore immediately cause a new key-pressed event to occur.
key_number_to_row_column(key_number: int) → Tuple[int]

Return the row and column for the given key number. The row is `key_number // len(column_pins)`. The column is `key_number % len(column_pins)`.

Returns
(row, column)

Return type
Tuple[int]

row_column_to_key_number(row: int, column: int) → int

Return the key number for a given row and column. The key number is `row * len(column_pins) + column`.

class keypad.Keys(pins: Sequence[microcontroller.Pin], *, value_when_pressed: bool, pull: bool = True, interval: float = 0.02, max_events: int = 64)

Manage a set of independent keys.

Create a `Keys` object that will scan keys attached to the given sequence of pins. Each key is independent and attached to its own pin.

An `EventQueue` is created when this object is created and is available in the `events` attribute.

Parameters

- **pins** (`Sequence[microcontroller.Pin]`) – The pins attached to the keys. The key numbers correspond to indices into this sequence.

- **value_when_pressed** (`bool`) – True if the pin reads high when the key is pressed. False if the pin reads low (is grounded) when the key is pressed. All the pins must be connected in the same way.

- **pull** (`bool`) – True if an internal pull-up or pull-down should be enabled on each pin. A pull-up will be used if `value_when_pressed` is False; a pull-down will be used if it is True. If an external pull is already provided for all the pins, you can set pull to False. However, enabling an internal pull when an external one is already present is not a problem; it simply uses slightly more current.

- **interval** (`float`) – Scan keys no more often than `interval` to allow for debouncing. `interval` is in float seconds. The default is 0.020 (20 msecs).

- **max_events** (`int`) – maximum size of `events EventQueue`: maximum number of key transition events that are saved. Must be >= 1. If a new event arrives when the queue is full, the oldest event is discarded.

key_count : int
The number of keys that are being scanned. (read-only)

events : EventQueue
The `EventQueue` associated with this `Keys` object. (read-only)

deinit() → None
Stop scanning and release the pins.

__enter__() → Keys
No-op used by Context Managers.

__exit__() → None
Automatically deinitializes when exiting a context. See *Lifetime and ContextManagers* for more info.
reset() → None

Reset the internal state of the scanner to assume that all keys are now released. Any key that is already pressed at the time of this call will therefore immediately cause a new key-pressed event to occur.

class keypad.ShiftRegisterKeys(*, clock: microcontroller.Pin, data: microcontroller.Pin, latch: microcontroller.Pin, value_to_latch: bool = True, key_count: int, value_when_pressed: bool, interval: float = 0.02, max_events: int = 64)

Manage a set of keys attached to an incoming shift register.

Create a Keys object that will scan keys attached to a parallel-in serial-out shift register like the 74HC165 or CD4021. Note that you may chain shift registers to load in as many values as you need.

Key number 0 is the first (or more properly, the zero-th) bit read. In the 74HC165, this bit is labeled Q7. Key number 1 will be the value of Q6, etc.

An EventQueue is created when this object is created and is available in the events attribute.

Parameters

- `clock` (microcontroller.Pin) – The shift register clock pin. The shift register should clock on a low-to-high transition.
- `data` (microcontroller.Pin) – The incoming shift register data pin.
- `latch` (microcontroller.Pin) – Pin used to latch parallel data going into the shift register.
- `value_to_latch` (bool) – Pin state to latch data being read. `True` if the data is latched when `latch` goes high. `False` if the data is latched when `latch` goes low. The default is `True`, which is how the 74HC165 operates. The CD4021 latch is the opposite. Once the data is latched, it will be shifted out by toggling the clock pin.
- `key_count` (int) – Number of data lines to clock in.
- `value_when_pressed` (bool) – `True` if the pin reads high when the key is pressed. `False` if the pin reads low (is grounded) when the key is pressed.
- `interval` (float) – Scan keys no more often than `interval` to allow for debouncing. `interval` is in float seconds. The default is 0.020 (20 msecs).
- `max_events` (int) – Maximum size of events EventQueue: maximum number of key transition events that are saved. Must be >= 1. If a new event arrives when the queue is full, the oldest event is discarded.

key_count : int

The number of keys that are being scanned. (read-only)

events : EventQueue

The EventQueue associated with this Keys object. (read-only)

dehinit() → None

Stop scanning and release the pins.

__enter__() → Keys

No-op used by Context Managers.

__exit__() → None

Automatically deinitializes when exiting a context. See Lifetime and ContextManagers for more info.

reset() → None

Reset the internal state of the scanner to assume that all keys are now released. Any key that is already pressed at the time of this call will therefore immediately cause a new key-pressed event to occur.
math – mathematical functions

The `math` module provides some basic mathematical functions for working with floating-point numbers.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: math.

```
math.e : float
    base of the natural logarithm

math.pi : float
    the ratio of a circle’s circumference to its diameter

math.acos(x : float) → float
    Return the inverse cosine of x.

math.asin(x : float) → float
    Return the inverse sine of x.

math.atan(x : float) → float
    Return the inverse tangent of x.

math.atan2(y : float, x : float) → float
    Return the principal value of the inverse tangent of y/x.

math.ceil(x : float) → int
    Return an integer, being x rounded towards positive infinity.

math.copysign(x : float, y : float) → float
    Return x with the sign of y.

math.cos(x : float) → float
    Return the cosine of x.

math.degrees(x : float) → float
    Return radians x converted to degrees.

math.exp(x : float) → float
    Return the exponential of x.

math.fabs(x : float) → float
    Return the absolute value of x.

math.floor(x : float) → int
    Return an integer, being x rounded towards negative infinity.

math.fmod(x : float, y : float) → int
    Return the remainder of x/y.

math.frexp(x : float) → Tuple[int, int]
    Decomposes a floating-point number into its mantissa and exponent. The returned value is the tuple (m, e) such that x == m * 2**e exactly. If x == 0 then the function returns (0.0, 0), otherwise the relation 0.5 <= abs(m) < 1 holds.

math.isfinite(x : float) → bool
    Return True if x is finite.
```
math.isinf(x: float) → bool
  Return True if x is infinite.

math.isnan(x: float) → bool
  Return True if x is not-a-number

math.ldexp(x: float, exp: float) → float
  Return x * (2**exp).

math.log(x: float, base: float = e) → float
  Return the logarithm of x to the given base. If base is not specified, returns the natural logarithm (base e) of x

math.modf(x: float) → Tuple[float, float]
  Return a tuple of two floats, being the fractional and integral parts of x. Both return values have the same sign as x.

math.pow(x: float, y: float) → float
  Returns x to the power of y.

math.radians(x: float) → float
  Return degrees x converted to radians.

math.sin(x: float) → float
  Return the sine of x.

math.sqrt(x: float) → float
  Returns the square root of x.

math.tan(x: float) → float
  Return the tangent of x.

math.trunc(x: float) → int
  Return an integer, being x rounded towards 0.

math.expm1(x: float) → float
  Return \( \exp(x) - 1 \).
  May not be available on some boards.

math.log2(x: float) → float
  Return the base-2 logarithm of x.
  May not be available on some boards.

math.log10(x: float) → float
  Return the base-10 logarithm of x.
  May not be available on some boards.

math.cosh(x: float) → float
  Return the hyperbolic cosine of x.
  May not be available on some boards.

math.sinh(x: float) → float
  Return the hyperbolic sine of x.
  May not be available on some boards.
math.tanh(x: float) → float
    Return the hyperbolic tangent of x.
    May not be available on some boards.

math.acosh(x: float) → float
    Return the inverse hyperbolic cosine of x.
    May not be available on some boards.

math.asinh(x: float) → float
    Return the inverse hyperbolic sine of x.
    May not be available on some boards.

math.atanh(x: float) → float
    Return the inverse hyperbolic tangent of x.
    May not be available on some boards.

math.erf(x: float) → float
    Return the error function of x.
    May not be available on some boards.

math.erfc(x: float) → float
    Return the complementary error function of x.
    May not be available on some boards.

math.gamma(x: float) → float
    Return the gamma function of x.
    May not be available on some boards.

math.lgamma(x: float) → float
    Return the natural logarithm of the gamma function of x.
    May not be available on some boards.

mdns – Multicast Domain Name Service

The mdns module provides basic support for multicast domain name services. Basic use provides hostname resolution under the .local TLD. This module also supports DNS Service Discovery that allows for discovering other hosts that provide a desired service.

class mdns.RemoteService
    Encapsulates information about a remote service that was found during a search. This object may only be created by a mdns.Server. It has no user-visible constructor.

    Cannot be instantiated directly. Use mdns.Server.find.

    hostname : str
        The hostname of the device (read-only).

    instance_name : str
        The human readable instance name for the service. (read-only)

    service_type : str
        The service type string such as _http. (read-only)
protocol :str
   The protocol string such as _tcp. (read-only)

port :int
   Port number used for the service. (read-only)

ipv4_address :Optional[ipaddress.IPv4Address]
   IP v4 Address of the remote service. None if no A records are found.

__del__() → None
   Deletes the RemoteService object.

class mdns.Server(network_interface: wifi.Radio)
   The MDNS Server responds to queries for this device’s information and allows for querying other devices. Constructs or returns the mdns.Server for the given network_interface. (CircuitPython may already be using it.) Only native interfaces are currently supported.

hostname :str
   Hostname resolvable as <hostname>.local in addition to circuitpython.local. Make sure this is unique across all devices on the network. It defaults to cpy-##### where ##### is the hex digits of the last three bytes of the mac address.

instance_name :str
   Human readable name to describe the device.

definit() → None
   Stops the server

find(service_type: str, protocol: str, *, timeout: float = 1) → Tuple[RemoteService]
   Find all locally available remote services with the given service type and protocol.
   This doesn’t allow for direct hostname lookup. To do that, use socketpool.SocketPool.getaddrinfo().

Parameters
   • service_type (str) – The service type such as “_http”
   • protocol (str) – The service protocol such as “_tcp”
   • timeout (float/int) – Time to wait for responses

advertise_service(*, service_type: str, protocol: str, port: int) → None
   Respond to queries for the given service with the given port.
   service_type and protocol can only occur on one port. Any call after the first will update the entry’s port.

Parameters
   • service_type (str) – The service type such as “_http”
   • protocol (str) – The service protocol such as “_tcp”
   • port (int) – The port used by the service
memorymonitor – Memory monitoring helpers

exception memorymonitor.AllocationError

    Bases: Exception

    Catchall exception for allocation related errors.
    Initialize self. See help(type(self)) for accurate signature.

class memorymonitor.AllocationAlarm(*, minimum_block_count: int = 1)

    Throw an exception when an allocation of minimum_block_count or more blocks
    occurs while active.

    Track allocations:

    ```python
    import memorymonitor
    aa = memorymonitor.AllocationAlarm(minimum_block_count=2)
    x = 2
    # Should not allocate any blocks.
    with aa:
        x = 5
    # Should throw an exception when allocating storage for the 20 bytes.
    with aa:
        x = bytearray(20)
    ```

    ignore(count: int) → AllocationAlarm

    Sets the number of applicable allocations to ignore before raising the exception. Automatically set back to
    zero at context exit.
    Use it within a with block:

    ```python
    # Will not alarm because the bytearray allocation will be ignored.
    with aa.ignore(2):
        x = bytearray(20)
    ```

    __enter__() → AllocationAlarm

    Enables the alarm.

    __exit__() → None

    Automatically disables the allocation alarm when exiting a context. See Lifetime and ContextManagers for
    more info.

class memorymonitor.AllocationSize

    Tracks the number of allocations in power of two buckets.

    It will have 16 16-bit buckets to track allocation counts. It is total allocations meaning frees are ignored. Real-
    located memory is counted twice, at allocation and when reallocated with the larger size.

    The buckets are measured in terms of blocks which is the finest granularity of the heap. This means bucket 0
    will count all allocations less than or equal to the number of bytes per block, typically 16. Bucket 2 will be less
    than or equal to 4 blocks. See bytes_per_block to convert blocks to bytes.

    Multiple AllocationSizes can be used to track different code boundaries.

    Track allocations:
```
import memorymonitor

mm = memorymonitor.AllocationSize()
with mm:
    print("hello world" * 3)

for bucket, count in enumerate(mm):
    print("<", 2 ** bucket, count)
```

**bytes_per_block : int**
Number of bytes per block

**__enter__() → AllocationSize**
Clears counts and resumes tracking.

**__exit__() → None**
Automatically pauses allocation tracking when exiting a context. See *Lifetime and ContextManagers* for more info.

**__len__() → int**
Returns the number of allocation buckets.

This allows you to:
```
mm = memorymonitor.AllocationSize()
print(len(mm))
```

**__getitem__(index: int) → Optional[int]**
Returns the allocation count for the given bucket.

This allows you to:
```
mm = memorymonitor.AllocationSize()
print(mm[0])
```

---

**microcontroller – Pin references and cpu functionality**

The `microcontroller` module defines the pins and other bare-metal hardware from the perspective of the microcontroller. See `board` for board-specific pin mappings.

**microcontroller/cpu : Processor**
CPU information and control, such as `cpu.temperature` and `cpu.frequency` (clock frequency). This object is an instance of `microcontroller.Processor`.

**microcontroller/cpu : Processor**
CPU information and control, such as `cpus[0].temperature` and `cpus[1].frequency` (clock frequency) on chips with more than 1 cpu. The index selects which cpu. This object is an instance of `microcontroller.Processor`.

**microcontroller/delay_us(delay: int) → None**
Dedicated delay method used for very short delays. **Do not** do long delays because this stops all other functions from completing. Think of this as an empty while loop that runs for the specified `delay` time. If you have other code or peripherals (e.g audio recording) that require specific timing or processing while you are waiting, explore a different avenue such as using `time.sleep()`.
microcontroller.disable_interrupts() → None
Disable all interrupts. Be very careful, this can stall everything.

microcontroller.enable_interrupts() → None
Enable the interrupts that were enabled at the last disable.

microcontroller.on_next_reset(run_mode: RunMode) → None
Configure the run mode used the next time the microcontroller is reset but not powered down.

Parameters
  run_mode (RunMode) – The next run mode

microcontroller.reset() → None
Reset the microcontroller. After reset, the microcontroller will enter the run mode last set by on_next_reset.

Warning: This may result in file system corruption when connected to a host computer. Be very careful when calling this! Make sure the device “Safely removed” on Windows or “ejected” on Mac OS X and Linux.

microcontroller.nvm :Optional[nvm.ByteArray]
Available non-volatile memory. This object is the sole instance of nvm.ByteArray when available or None otherwise.

  Type
    nvm.ByteArray or None

microcontroller.watchdog :Optional[watchdog.WatchDogTimer]
Available watchdog timer. This object is the sole instance of watchdog.WatchDogTimer when available or None otherwise.

class microcontroller.Pin
Identifies an IO pin on the microcontroller.

Identifies an IO pin on the microcontroller. They are fixed by the hardware so they cannot be constructed on demand. Instead, use board or microcontroller.pin to reference the desired pin.

__hash__() → int
Returns a hash for the Pin.

class microcontroller.Processor
Microcontroller CPU information and control

Usage:

```python
import microcontroller
print(microcontroller.cpu.frequency)
print(microcontroller.cpu.temperature)
```

Note that on chips with more than one cpu (such as the RP2040) microcontroller.cpu will return the value for CPU 0.
To get values from other CPUs use microcontroller cpus indexed by the number of the desired cpu. i.e.

```python
print(microcontroller.cpus[0].temperature)
print(microcontroller.cpus[1].frequency)
```
You cannot create an instance of `microcontroller.Processor`. Use `microcontroller.cpu` to access the sole instance available.

**frequency :int**
The CPU operating frequency in Hertz. (read-only)

**reset_reason :ResetReason**
The reason the microcontroller started up from reset state.

**temperature :Optional[float]**
The on-chip temperature, in Celsius, as a float. (read-only)

Is `None` if the temperature is not available.

**Limitations:** Not available on ESP32 or ESP32-S3. On small SAMD21 builds without external flash, the reported temperature has reduced accuracy and precision, to save code space.

**uid :bytearray**
The unique id (aka serial number) of the chip as a `bytearray`. (read-only)

**voltage :Optional[float]**
The input voltage to the microcontroller, as a float. (read-only)

Is `None` if the voltage is not available.

---

**class microcontroller.ResetReason**
The reason the microcontroller was last reset

**POWER_ON :object**
The microcontroller was started from power off.

**BROWNOUT :object**
The microcontroller was reset due to too low a voltage.

**SOFTWARE :object**
The microcontroller was reset from software.

**DEEP_SLEEP_ALARM :object**
The microcontroller was reset for deep sleep and restarted by an alarm.

**RESET_PIN :object**
The microcontroller was reset by a signal on its reset pin. The pin might be connected to a reset button.

**WATCHDOG :object**
The microcontroller was reset by its watchdog timer.

**UNKNOWN :object**
The microcontroller restarted for an unknown reason.

**RESCUE_DEBUG :object**
The microcontroller was reset by the rescue debug port.

---

**class microcontroller.RunMode**
run state of the microcontroller

Enum-like class to define the run mode of the microcontroller and CircuitPython.

**NORMAL :RunMode**
Run CircuitPython as normal.
SAFE_MODE :RunMode
Run CircuitPython in safe mode. User code will not run and the file system will be writeable over USB.

UF2 :RunMode
Run the uf2 bootloader.

BOOTLOADER :RunMode
Run the default bootloader.

msgpack – Pack object in msgpack format

The msgpack format is similar to json, except that the encoded data is binary. See https://msgpack.org for details. The module implements a subset of the cpython module msgpack-python.
Not implemented: 64-bit int, uint, float.
For more information about working with msgpack, see the CPython Library Documentation.

Example 1:

```python
import msgpack
from io import BytesIO

b = BytesIO()
msgpack.pack({'list': [True, False, None, 1, 3.14], 'str': 'blah'}, b)
b.seek(0)
print(msgpack.unpack(b))
```

Example 2: handling objects:

```python
from msgpack import pack, unpack, ExtType
from io import BytesIO

class MyClass:
    def __init__(self, val):
        self.value = val
    def __str__(self):
        return str(self.value)
data = MyClass(b'my_value')

def encoder(obj):
    if isinstance(obj, MyClass):
        return ExtType(1, obj.value)
    return f'no encoder for {obj}'

def decoder(code, data):
    if code == 1:
        return MyClass(data)
    return f'no decoder for type {code}'
```

(continues on next page)
buffer = BytesIO()
pack(data, buffer, default=encoder)
buffer.seek(0)
decoded = unpack(buffer, ext_hook=decoder)
print(f"{data} -> {buffer.getvalue()} -> {decoded}"

msgpack.pack(obj: object, stream: circuitpython_typing.ByteStream, *, default: Union[Callable[[object], None], None] = None) → None

Output object to stream in msgpack format.

Parameters
- obj (object) – Object to convert to msgpack format.
- stream (ByteStream) – stream to write to
- default (Optional[Callable[[object], None]]) – function called for python objects that do not have a representation in msgpack format.

msgpack.unpack(stream: circuitpython_typing.ByteStream, *, ext_hook: Union[Callable[[int, bytes], object], None] = None, use_list: bool = True) → object

Unpack and return one object from stream.

Parameters
- stream (ByteStream) – stream to read from
- ext_hook (Optional[Callable[[int, bytes], object]]) – function called for objects in msgpack ext format.
- use_list (Optional[bool]) – return array as list or tuple (use_list=True).

Return object
object read from stream.

class msgpack.ExtType(code: int, data: bytes)

ExtType represents ext type in msgpack.

Constructor
:param int code: type code in range 0~127. :param bytes data: representation.

code :int
The type code, in range 0~127.

data :bytes
Data.

neopixel_write – Low-level neopixel implementation

The neopixel_write module contains a helper method to write out bytes in the 800khz neopixel protocol.

For example, to turn off a single neopixel (like the status pixel on Express boards.)

import board
import neopixel_write
import digitalio

(continues on next page)
```python
pin = digitalio.DigitalInOut(board.NEOPIXEL)
pin.direction = digitalio.Direction.OUTPUT
pixel_off = bytearray([0, 0, 0])
neopixel_write.neopixel_write(pin, pixel_off)
```

**Note:** This module is typically not used by user level code.

For more information on actually using NeoPixels, refer to the [CircuitPython Essentials Learn guide](#).

For a much more thorough guide about using NeoPixels, refer to the Adafruit NeoPixel Überguide.

```python
neopixel_write.neopixel_write(digitalinout: digitalio.DigitalInOut, buf:
circuitpython_typing.ReadableBuffer) → None
```

Write buf out on the given DigitalInOut.

**Parameters**

- `digitalinout` ([DigitalInOut](#)) – the DigitalInOut to output with
- `buf` ([ReadableBuffer](#)) – The bytes to clock out. No assumption is made about color order

### nvm – Non-volatile memory

The `nvm` module allows you to store whatever raw bytes you wish in a reserved section non-volatile memory.

Note that this module can’t be imported and used directly. The sole instance of `ByteArray` is available at `microcontroller.nvm`.

```python
class nvm.ByteArray
```

Presents a stretch of non-volatile memory as a bytearray.

Non-volatile memory is available as a byte array that persists over reloads and power cycles. Each assignment causes an erase and write cycle so its recommended to assign all values to change at once.

**Usage:**

```python
import microcontroller
microcontroller.nvm[0:3] = b"\xc0\x10\x00"
```

Not currently dynamically supported. Access the sole instance through `microcontroller.nvm`.

- `__bool__()` → bool
- `__len__()` → int
  
  Return the length. This is used by `(len)`
- `__getitem__(index: slice) → bytearray`
- `__getitem__(index: int) → int`
  
  Returns the value at the given index.
- `__setitem__(index: slice, value: circuitpython_typing.ReadableBuffer) → None`
- `__setitem__(index: int, value: int) → None`
  
  Set the value at the given index.
onewireio – Low-level bit primitives for Maxim (formerly Dallas Semi) one-wire protocol.


class onewireio.OneWire(pin: microcontroller.Pin)
    Create a OneWire object associated with the given pin.
    The object implements the lowest level timing-sensitive bits of the protocol.
    Parameters
    pin (Pin) – Pin connected to the OneWire bus

Read a short series of pulses:

import onewireio
import board

onewire = onewireio.OneWire(board.D7)
onewire.reset()
onewire.write_bit(True)
onewire.write_bit(False)
print(onewire.read_bit())


deinit() → None
    Deinitialize the OneWire bus and release any hardware resources for reuse.

__enter__() → OneWire
    No-op used by Context Managers.

__exit__() → None
    Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

reset() → bool
    Reset the OneWire bus and read presence

    Returns
    False when at least one device is present

    Return type
    bool

read_bit() → bool
    Read in a bit

    Returns
    bit state read

    Return type
    bool

write_bit(value: bool) → None
    Write out a bit based on value.
os – functions that an OS normally provides

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: os.

```python
os.uname() → _Uname
```

Returns a named tuple of operating specific and CircuitPython port specific information.

```python
class os._Uname
    Bases: NamedTuple
    The type of values that uname() returns
    
    sysname : str
    nodename : str
    release : str
    version : str
    machine : str
```

```python
os.chdir(path: str) → None
```
Change current directory.

```python
os.getcwd() → str
```
Get the current directory.

```python
os.getenv(key: str, default: Optional[str] = None) → Optional[str]
```
Get the environment variable value for the given key or return default. This may load values from disk so cache the result instead of calling this often.

```python
os.listdir(dir: str) → str
```
With no argument, list the current directory. Otherwise list the given directory.

```python
os.mkdir(path: str) → None
```
Create a new directory.

```python
os.remove(path: str) → None
```
Remove a file.

```python
os.rmdir(path: str) → None
```
Remove a directory.

```python
os.rename(old_path: str, new_path: str) → str
```
Rename a file.

```python
os.stat(path: str) → Tuple[int, int, int, int, int, int, int, int]
```
Get the status of a file or directory.

Returns a tuple with the status of a file or directory in the following order:

- `st_mode` – File type, regular or directory
- `st_ino` – Set to 0
- `st_dev` – Set to 0
- `st_nlink` – Set to 0
• st_uid – Set to 0
• st_gid – Set to 0
• st_size – Size of the file in bytes
• st_atime – Time of most recent access expressed in seconds
• st_mtime – Time of most recent content modification expressed in seconds.
• st_ctime – Time of most recent content modification expressed in seconds.

Note: On builds without long integers, the number of seconds for contemporary dates will not fit in a small integer. So the time fields return 946684800, which is the number of seconds corresponding to 1999-12-31.

\[\text{os.statvfs}(\text{path}: \text{str}) \rightarrow \text{Tuple}[\text{int, int, int, int, int, int, int, int, int, int}]\]

Get the status of a filesystem.

Returns a tuple with the filesystem information in the following order:

• f_bsize – file system block size
• f_frsize – fragment size
• f_blocks – size of fs in f_frsize units
• f_bfree – number of free blocks
• f_bavail – number of free blocks for unprivileged users
• f_files – number of inodes
• f_ffree – number of free inodes
• f_favail – number of free inodes for unprivileged users
• f_flag – mount flags
• f_namemax – maximum filename length

Parameters related to inodes: f_files, f_ffree, f_favail and the f_flag parameter may return 0 as they can be unavailable in a port-specific implementation.

\[\text{os.sync}() \rightarrow \text{None}\]

Sync all filesystems.

\[\text{os.urandom}(\text{size}: \text{int}) \rightarrow \text{str}\]

Returns a string of size random bytes based on a hardware True Random Number Generator. When not available, it will raise a \text{NotImplementedError}.

Limitations: Not yet available on nRF. Not available on SAMD21 due to lack of hardware.

\[\text{os.utime}(\text{path}: \text{str}, \text{times}: \text{Tuple}[\text{int, int}]) \rightarrow \text{None}\]

Change the timestamp of a file.

\[\text{os.sep :str}\]

Separator used to delineate path components such as folder and file names.
**paralleldisplay** – Native helpers for driving parallel displays

```python
```

Manage updating a display over 8-bit parallel bus in the background while Python code runs. This protocol may be referred to as 8080-I Series Parallel Interface in datasheets. It doesn’t handle display initialization.

Create a ParallelBus object associated with the given pins. The bus is inferred from data0 by implying the next 7 additional pins on a given GPIO port.

The parallel bus and pins are then in use by the display until `displayio.release_displays()` is called even after a reload. (It does this so CircuitPython can use the display after your code is done.) So, the first time you initialize a display bus in code.py you should call `displayio.release_displays()` first, otherwise it will error after the first code.py run.

**Parameters**

- `data_pins` ([`microcontroller.Pin`]) – A list of data pins. Specify exactly one of `data_pins` or `data0`.
- `data0` ([`microcontroller.Pin`]) – The first data pin. The rest are implied
- `command` ([`microcontroller.Pin`]) – Data or command pin
- `chip_select` ([`microcontroller.Pin`]) – Chip select pin
- `write` ([`microcontroller.Pin`]) – Write pin
- `read` ([`microcontroller.Pin`]) – Read pin, optional
- `reset` ([`microcontroller.Pin`]) – Reset pin, optional
- `frequency` (`int`) – The communication frequency in Hz for the display on the bus

```python
reset() → None
```

Performs a hardware reset via the reset pin. Raises an exception if called when no reset pin is available.

```python
send(command: int, data: circuitpython_typing.ReadableBuffer) → None
```

Sends the given command value followed by the full set of data. Display state, such as vertical scroll, set via `send` may or may not be reset once the code is done.

**ps2io** – Support for PS/2 protocol

The `ps2io` module contains classes to provide PS/2 communication.

**Warning:** This module is not available in some SAMD21 builds. See the [Module Support Matrix - Which Modules Are Available on Which Boards](#) for more info.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See [Lifetime and Context Managers](#) for more info.

```python
class ps2io.Ps2(data_pin: microcontroller.Pin, clock_pin: microcontroller.Pin)

Communicate with a PS/2 keyboard or mouse
```
Ps2 implements the PS/2 keyboard/mouse serial protocol, used in legacy devices. It is similar to UART but there are only two lines (Data and Clock). PS/2 devices are 5V, so bidirectional level converters must be used to connect the I/O lines to pins of 3.3V boards.

Create a Ps2 object associated with the given pins.

**Parameters**
- `data_pin` (Pin) – Pin tied to data wire.
- `clock_pin` (Pin) – Pin tied to clock wire. This pin must support interrupts.

Read one byte from PS/2 keyboard and turn on Scroll Lock LED:

```python
import ps2io
import board

kbd = ps2io.Ps2(board.D10, board.D11)

while len(kbd) == 0:
    pass

print(kbd.popleft())
print(kbd.sendcmd(0xed))
print(kbd.sendcmd(0x01))

definit() → None
    Deinitialises the Ps2 and releases any hardware resources for reuse.

__enter__() → Ps2
    No-op used by Context Managers.

__exit__() → None
    Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

popleft() → int
    Removes and returns the oldest received byte. When buffer is empty, raises an IndexError exception.

sendcmd(byte: int) → int
    Sends a command byte to PS/2. Returns the response byte, typically the general ack value (0xFA). Some commands return additional data which is available through `popleft()`.

    Raises a RuntimeError in case of failure. The root cause can be found by calling `clear_errors()`. It is advisable to call `clear_errors()` before `sendcmd()` to flush any previous errors.

    **Parameters**
    - `byte (int)` – byte value of the command

    clear_errors() → None
    Returns and clears a bitmap with latest recorded communication errors.

    Reception errors (arise asynchronously, as data is received):
    0x01: start bit not 0
    0x02: timeout
    0x04: parity bit error
    0x08: stop bit not 1
Transmission errors (can only arise in the course of sendcmd()):

- 0x10: buffer overflow, newest data discarded
- 0x100: clock pin didn’t go to LO in time
- 0x200: clock pin didn’t go to HI in time
- 0x400: data pin didn’t ACK
- 0x800: clock pin didn’t ACK
- 0x1000: device didn’t respond to RTS
- 0x2000: device didn’t send a response byte in time

__bool__() → bool

__len__() → int

Returns the number of received bytes in buffer, available to popleft().

## pulseio – Support for individual pulse based protocols

The **pulseio** module contains classes to provide access to basic pulse IO. Individual pulses are commonly used in infrared remotes and in DHT temperature sensors.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call deinit() or use a context manager. See *Lifetime and ContextManagers* for more info.

**class** pulseio.PulseIn(pin: microcontroller.Pin, maxlen: int = 2, *, idle_state: bool = False)

Measure a series of active and idle pulses. This is commonly used in infrared receivers and low cost temperature sensors (DHT). The pulsed signal consists of timed active and idle periods. Unlike PWM, there is no set duration for active and idle pairs.

Create a PulseIn object associated with the given pin. The object acts as a read-only sequence of pulse lengths with a given max length. When it is active, new pulse lengths are added to the end of the list. When there is no more room (len() == maxlen) the oldest pulse length is removed to make room.

**Parameters**

- **pin (Pin)** – Pin to read pulses from.
- **maxlen (int)** – Maximum number of pulse durations to store at once
- **idle_state (bool)** – Idle state of the pin. At start and after resume the first recorded pulse will the opposite state from idle.

Read a short series of pulses:

```python
import pulseio
import board

pulses = pulseio.PulseIn(board.D7)

# Wait for an active pulse
while len(pulses) == 0:
    pass

# Pause while we do something with the pulses
pulses.pause()
```

(continues on next page)
# Print the pulses. pulses[0] is an active pulse unless the length
# reached max length and idle pulses are recorded.
print(pulses)

# Clear the rest
pulses.clear()

# Resume with an 80 microsecond active pulse
pulses.resume(80)

maxlen : int
   The maximum length of the PulseIn. When len() is equal to maxlen, it is unclear which pulses are active
   and which are idle.

paused : bool
   True when pulse capture is paused as a result of `pause()` or an error during capture such as a signal that
   is too fast.

deinit() → None
   Deinitialises the PulseIn and releases any hardware resources for reuse.

__enter__() → PulseIn
   No-op used by Context Managers.

__exit__() → None
   Automatically deinitializes the hardware when exiting a context. See `Lifetime and ContextManagers` for
   more info.

pause() → None
   Pause pulse capture

resume(trigger_duration: int = 0) → None
   Resumes pulse capture after an optional trigger pulse.

**Warning:** Using trigger pulse with a device that drives both high and low signals risks a short. Make
sure your device is open drain (only drives low) when using a trigger pulse. You most likely added a
“pull-up” resistor to your circuit to do this.

**Parameters**

`trigger_duration` (int) – trigger pulse duration in microseconds

clear() → None
   Clears all captured pulses

popleft() → int
   Removes and returns the oldest read pulse.

__bool__() → bool

__len__() → int
   Returns the number of pulse durations currently stored.

This allows you to:
```python
pulses = pulseio.PulseIn(pin)
print(len(pulses))
```

```python
__getitem__(index: int) → Optional[int]
Returns the value at the given index or values in slice.
This allows you to:
```  
```python
pulses = pulseio.PulseIn(pin)
print(pulses[0])
```

```python
class pulseio.PulseOut(
    pin: microcontroller.Pin,
    *,
    frequency: int = 38000,
    duty_cycle: int = 1 << 15
)
Pulse PWM “carrier” output on and off. This is commonly used in infrared remotes. The pulsed signal consists of timed on and off periods. Unlike PWM, there is no set duration for on and off pairs.

Create a PulseOut object associated with the given pin.

Parameters

- **pin** (Pin) – Signal output pin
- **frequency** (int) – Carrier signal frequency in Hertz
- **duty_cycle** (int) – 16-bit duty cycle of carrier frequency (0 - 65536)

Send a short series of pulses:

```python
import array
import pulseio
import pwmio
import board

# 50% duty cycle at 38kHz.
pulse = pulseio.PulseOut(board.LED, frequency=38000, duty_cycle=32768)
# on off on off on
pulses = array.array('H', [65000, 1000, 65000, 65000, 1000])
pulse.send(pulses)

# Modify the array of pulses.
pulses[0] = 200
pulse.send(pulses)
```

```python
deinit() → None
Deinitialises the PulseOut and releases any hardware resources for reuse.
```

```python
__enter__() → PulseOut
No-op used by Context Managers.
```

```python
__exit__() → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.
```

```python
send(pulses: circuitpython_typing.ReadableBuffer) → None
Pulse alternating on and off durations in microseconds starting with on. pulses must be an array.array with data type ‘H’ for unsigned halfword (two bytes).

This method waits until the whole array of pulses has been sent and ensures the signal is off afterwards.
```
Parameters

- **pulses** *(array.array)* – pulse durations in microseconds

**pwmio – Support for PWM based protocols**

The `pwmio` module contains classes to provide access to basic pulse IO.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See *Lifetime and ContextManagers* for more info.

For example:

```python
import time
import pwmio
import board

pwm = pwmio.PWMOut(board.LED)
pwm.duty_cycle = 2 ** 15
time.sleep(0.1)
```

This example will initialize the device, set `duty_cycle`, and then sleep 0.1 seconds. CircuitPython will automatically turn off the PWM when it resets all hardware after program completion. Use `deinit()` or a `with` statement to do it yourself.

For the essentials of `pwmio`, see the CircuitPython Essentials Learn guide.

```python
class pwmio.PWMOut(pin: microcontroller.Pin, *, duty_cycle: int = 0, frequency: int = 500, variable_frequency: bool = False)

Output a Pulse Width Modulated signal on a given pin.

Create a PWM object associated with the given pin. This allows you to write PWM signals out on the given pin. Frequency is fixed after init unless `variable_frequency` is True.
```

**Note:** When `variable_frequency` is True, further PWM outputs may be limited because it may take more internal resources to be flexible. So, when outputting both fixed and flexible frequency signals construct the fixed outputs first.

**Parameters**

- **pin** *(Pin)* – The pin to output to
- **duty_cycle** *(int)* – The fraction of each pulse which is high. 16-bit
- **frequency** *(int)* – The target frequency in Hertz (32-bit)
- **variable_frequency** *(bool)* – True if the frequency will change over time

Simple LED on:

```python
import pwmio
import board

pwm = pwmio.PWMOut(board.LED)
while True:
```

(continues on next page)
pwm.duty_cycle = 2 ** 15  # Cycles the pin with 50% duty cycle (half of 2 ** 16) at the default 500hz

PWM LED fade:

```python
import pwmio
import board

pwm = pwmio.PWMOut(board.LED)  # output on LED pin with default of 500Hz

while True:
    for cycle in range(0, 65535):
        pwm.duty_cycle = cycle  # Cycles the LED pin duty cycle through the range of values
    for cycle in range(65534, 0, -1):
        pwm.duty_cycle = cycle  # Cycles the LED pin duty cycle through the range of values

PWM at specific frequency (servos and motors):

```python
import pwmio
import board

pwm = pwmio.PWMOut(board.D13, frequency=50)
pwm.duty_cycle = 2 ** 15  # Cycles the pin with 50% duty cycle (half of 2 ** 16) at 50hz

Variable frequency (usually tones):

```python
import pwmio
import board
import time

pwm = pwmio.PWMOut(board.D13, duty_cycle=2 ** 15, frequency=440, variable_frequency=True)
time.sleep(0.2)
pwm.frequency = 880
time.sleep(0.1)
```

duty_cycle : int

16 bit value that dictates how much of one cycle is high (1) versus low (0). 0xffff will always be high, 0 will always be low and 0x7fff will be half high and then half low.

Depending on how PWM is implemented on a specific board, the internal representation for duty cycle might have less than 16 bits of resolution. Reading this property will return the value from the internal representation, so it may differ from the value set.

frequency : int

32 bit value that dictates the PWM frequency in Hertz (cycles per second). Only writeable when constructed with variable_frequency=True.

Depending on how PWM is implemented on a specific board, the internal value for the PWM’s duty cycle may need to be recalculated when the frequency changes. In these cases, the duty cycle is automatically

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recalculated from the original duty cycle value. This should happen without any need to manually re-set the duty cycle.

```python
definit() → None
```
Deinitialises the PWMOut and releases any hardware resources for reuse.

```python
__enter__() → PWMOut
```
No-op used by Context Managers.

```python
__exit__() → None
```
Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.

### qrio – Low-level QR code decoding

Provides the `QRDecoder` object used for decoding QR codes. For more information about working with QR codes, see this Learn guide.

**Note:** This module only handles decoding QR codes. If you are looking to generate a QR code, use the *adafruit_miniqur* library

```python
class qrio.PixelPolicy
```

**EVERY_BYTE :** PixelPolicy
The input buffer to `QRDecoder.decode` consists of greyscale values in every byte

**EVEN_BYTES :** PixelPolicy
The input buffer to `QRDecoder.decode` consists of greyscale values in positions 0, 2, ..., and ignored bytes in positions 1, 3, .... This can decode directly from YUV images where the even bytes hold the Y (luminance) data.

**ODD_BYTES :** PixelPolicy
The input buffer to `QRDecoder.decode` consists of greyscale values in positions 1, 3, ..., and ignored bytes in positions 0, 2, .... This can decode directly from YUV images where the odd bytes hold the Y (luminance) data

**RGB565_SWAPPED :** PixelPolicy
The input buffer to `QRDecoder.decode` consists of RGB565 values in byte-swapped order. Most cameras produce data in byte-swapped order. The green component is used.

**RGB565 :** PixelPolicy
The input buffer to `QRDecoder.decode` consists of RGB565 values in native order. The green component is used.

```python
class qrio.QRDecoder(width: int, height: int)
```
Construct a QRDecoder object

**Parameters**
- **width (int)** – The pixel width of the image to decode
- **height (int)** – The pixel height of the image to decode

**width :** int
The width of image the decoder expects
height : int
    The height of image the decoder expects

    Decode zero or more QR codes from the given image. The size of the buffer must be at least
    `length × width` bytes for EVERY_BYTE, and `2 × length × width` bytes for EVEN_BYTES or
    ODD_BYTES.

class qrio.QRInfo
    Information about a decoded QR code

    payload : bytes
        The content of the QR code

    data_type : Union[str, int]
        The encoding of the payload as a string (if a standard encoding) or int (if not standard)

rainbowio

rainbowio module.

Provides the colorwheel() function.

rainbowio.colorwheel(n: float) → int
    C implementation of the common colorwheel() function found in many examples. Returns the colorwheel RGB
    value as an integer value for n (usable in neopixel and dotstar).

random – pseudo-random numbers and choices

This module implements a subset of the corresponding CPython module, as described below. For more information,
refer to the original CPython documentation: random.

Like its CPython cousin, CircuitPython’s random seeds itself on first use with a true random from os.urandom() when
available or the uptime otherwise. Once seeded, it will be deterministic, which is why its bad for cryptography.

Warning: Numbers from this module are not cryptographically strong! Use bytes from os.urandom directly for
true randomness.

random._T

random.seed(seed: int) → None
    Sets the starting seed of the random number generation. Further calls to random will return deterministic results
    afterwards.

random.getrandbits(k: int) → int
    Returns an integer with k random bits.

random.randrange(stop: int) → int
random.randrange(start: int, stop: int) → int
random.randrange(start: int, stop: int, step: int) → int
    Returns a randomly selected integer from range([start[, stop[, step]]]).

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random.randint(a: int, b: int) → int

Returns a randomly selected integer between a and b inclusive. Equivalent to randrange(a, b + 1, 1)

random.choice(seq: Sequence[_T]) → _T

Returns a randomly selected element from the given sequence. Raises IndexError when the sequence is empty.

random.random() → float

Returns a random float between 0 and 1.0.

random.uniform(a: float, b: float) → float

Returns a random float between a and b. It may or may not be inclusive depending on float rounding.

rgbmatrix – Low-level routines for bitbanged LED matrices


Displays an in-memory framebuffer to a HUB75-style RGB LED matrix.

Create a RGBMatrix object with the given attributes. The height of the display is determined by the number of rgb and address pins and the number of tiles: len(rgb_pins) // 3 * 2 ** len(address_pins) * abs(tile). With 6 RGB pins, 4 address lines, and a single matrix, the display will be 32 pixels tall. If the optional height parameter is specified and is not 0, it is checked against the calculated height.

Up to 30 RGB pins and 8 address pins are supported.

The RGB pins must be within a single “port” and performance and memory usage are best when they are all within “close by” bits of the port. The clock pin must also be on the same port as the RGB pins. See the documentation of the underlying protomatter C library for more information. Generally, Adafruit’s interface boards are designed so that these requirements are met when matched with the intended microcontroller board. For instance, the Feather M4 Express works together with the RGB Matrix Feather.

The framebuffer is in “RGB565” format.

“RGB565” means that it is organized as a series of 16-bit numbers where the highest 5 bits are interpreted as red, the next 6 as green, and the final 5 as blue. The object can be any buffer, but array.array and ulab.ndarray objects are most often useful. To update the content, modify the framebuffer and call refresh.

If a framebuffer is not passed in, one is allocated and initialized to all black. In any case, the framebuffer can be retrieved by passing the RGBMatrix object to memoryview().

If doublebuffer is False, some memory is saved, but the display may flicker during updates.

A RGBMatrix is often used in conjunction with a framebufferio.FramebufferDisplay.

brightness : float

In the current implementation, 0.0 turns the display off entirely and any other value up to 1.0 turns the display on fully.

width : int

The width of the display, in pixels

height : int

The height of the display, in pixels
**deinit**() → None

Free the resources (pins, timers, etc.) associated with this rgbmatrix instance. After deinitialization, no further operations may be performed.

**refresh**() → None

Transmits the color data in the buffer to the pixels so that they are shown.

---

**rotaryio** – Support for reading rotation sensors

The *rotaryio* module contains classes to read different rotation encoding schemes. See [Wikipedia’s Rotary Encoder page](https://en.wikipedia.org/wiki/Rotary_encoder) for more background.

For more information on working with rotary encoders using this library, see [this Learn Guide](https://learn.adafruit.com/rotary-encoder).

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call **deinit**() or use a context manager. See [Lifetime and ContextManagers](https://docs.python.org/3/library/contextlib.html) for more info.

```python
    IncrementalEncoder determines the relative rotational position based on two series of pulses.

    Create an IncrementalEncoder object associated with the given pins. It tracks the positional state of an incremental rotary encoder (also known as a quadrature encoder.) Position is relative to the position when the object is constructed.

    Parameters
    • **pin_a** (*Pin*) – First pin to read pulses from.
    • **pin_b** (*Pin*) – Second pin to read pulses from.
    • **divisor** (*int*) – The divisor of the quadrature signal.

    For example:

    ```python
    import rotaryio
    import time
    from board import *

    enc = rotaryio.IncrementalEncoder(D1, D2)
    last_position = None
    while True:
        position = enc.position
        if last_position == None or position != last_position:
            print(position)
        last_position = position
    ```

    **divisor** : *int*

    The divisor of the quadrature signal. Use 1 for encoders without detents, or encoders with 4 detents per cycle. Use 2 for encoders with 2 detents per cycle. Use 4 for encoders with 1 detent per cycle.

    **position** : *int*

    The current position in terms of pulses. The number of pulses per rotation is defined by the specific hardware and by the divisor.

    **deinit**() → None

    Deinitializes the IncrementalEncoder and releases any hardware resources for reuse.
__enter__() → IncrementalEncoder
No-op used by Context Managers.

__exit__() → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

**rp2pio** – Hardware interface to RP2 series' programmable IO (PIO) peripheral.

Note: This module is intended to be used with the adafruit_pioasm library. For an introduction and guide to working with PIO in CircuitPython, see this Learn guide.

```python
rp2pio.pins_are_sequential(pins: List[microcontroller.Pin]) → bool
    Return True if the pins have sequential GPIO numbers, False otherwise

```

A single PIO StateMachine

The programmable I/O peripheral on the RP2 series of microcontrollers is unique. It is a collection of generic state machines that can be used for a variety of protocols. State machines may be independent or coordinated. Program memory and IRQs are shared between the state machines in a particular PIO instance. They are independent otherwise.

This class is designed to facilitate sharing of PIO resources. By default, it is assumed that the state machine is used on its own and can be placed in either PIO. State machines with the same program will be placed in the same PIO if possible.

Construct a StateMachine object on the given pins with the given program.

**Parameters**

- **program** *(ReadableBuffer)* – the program to run with the state machine
- **frequency** *(int)* – the target clock frequency of the state machine. Actual may be less. Use 0 for system clock speed.
- **init** *(ReadableBuffer)* – a program to run once at start up. This is run after program is started so instructions may be intermingled
- **first_out_pin** *(Pin)* – the first pin to use with the OUT instruction
- **out_pin_count** *(int)* – the count of consecutive pins to use with OUT starting at `first_out_pin`
- **initial_out_pin_state** *(int)* – the initial output value for out pins starting at `first_out_pin`
- **initial_out_pin_direction** *(int)* – the initial output direction for out pins starting at `first_out_pin`
- **first_in_pin** *(Pin)* – the first pin to use with the IN instruction
- **in_pin_count** *(int)* – the count of consecutive pins to use with IN starting at `first_in_pin`
- **pull_in_pin_up** *(int)* – a 1-bit in this mask sets pull up on the corresponding in pin
- **pull_in_pin_down** *(int)* – a 1-bit in this mask sets pull down on the corresponding in pin. Setting both pulls enables a “bus keep” function, i.e. a weak pull to whatever is current high/low state of GPIO.
- **first_set_pin** *(Pin)* – the first pin to use with the SET instruction
- **set_pin_count** *(int)* – the count of consecutive pins to use with SET starting at `first_set_pin`
- **initial_set_pin_state** *(int)* – the initial output value for set pins starting at `first_set_pin`
- **initial_set_pin_direction** *(int)* – the initial output direction for set pins starting at `first_set_pin`
- **first_sideset_pin** *(Pin)* – the first pin to use with a side set
- **sideset_pin_count** *(int)* – the count of consecutive pins to use with a side set starting at `first_sideset_pin`. Does not include sideset enable
- **initial_sideset_pin_state** *(int)* – the initial output value for sideset pins starting at `first_sideset_pin`
- **initial_sideset_pin_direction** *(int)* – the initial output direction for sideset pins starting at `first_sideset_pin`
- **sideset_enable** *(bool)* – True when the top sideset bit is to enable. This should be used with the “.side_set # opt” directive
- **jmp_pin** *(Pin)* – the pin which determines the branch taken by JMP PIN instructions
- **jmp_pin_pull** *(Pull)* – The pull value for the jmp pin, default is no pull.
- **exclusive_pin_use** *(bool)* – When True, do not share any pins with other state machines. Pins are never shared with other peripherals
- **auto_pull** *(bool)* – When True, automatically load data from the tx FIFO into the output shift register (OSR) when an OUT instruction shifts more than pull_threshold bits
- **pull_threshold** *(int)* – Number of bits to shift before loading a new value into the OSR from the tx FIFO
- **out_shift_right** *(bool)* – When True, data is shifted out the right side (LSB) of the OSR. It is shifted out the left (MSB) otherwise. NOTE! This impacts data alignment when the number of bytes is not a power of two (1, 2 or 4 bytes).
- **wait_for_txstall** *(bool)* – When True, writing data out will block until the TX FIFO and OSR are empty and an instruction is stalled waiting for more data. When False, data writes won’t wait for the OSR to empty (only the TX FIFO) so make sure you give enough time before deiniting or stopping the state machine.
• **auto_push** *(bool)* – When True, automatically save data from input shift register (ISR) into the rx FIFO when an IN instruction shifts more than push_threshold bits

• **push_threshold** *(int)* – Number of bits to shift before saving the ISR value to the RX FIFO

• **in_shift_right** *(bool)* – When True, data is shifted into the right side (LSB) of the ISR. It is shifted into the left (MSB) otherwise. NOTE! This impacts data alignment when the number of bytes is not a power of two (1, 2 or 4 bytes).

• **user_interruptible** *(bool)* – When True (the default), write(), readinto(), and write_readinto() can be interrupted by a ctrl-C. This is useful when developing a PIO program: if there is an error in the program that causes an infinite loop, you will be able to interrupt the loop. However, if you are writing to a device that can get into a bad state if a read or write is interrupted, you may want to set this to False after your program has been vetted.

• **wrap_target** *(int)* – The target instruction number of automatic wrap. Defaults to the first instruction of the program.

• **wrap** *(int)* – The instruction after which to wrap to the wrap instruction. As a special case, -1 (the default) indicates the last instruction of the program.

writing :bool
   Returns True if a background write is in progress

pending :int
   Returns the number of pending buffers for background writing.

   If the number is 0, then a StateMachine.background_write call will not block.

frequency :int
   The actual state machine frequency. This may not match the frequency requested due to internal limitations.

txstall :bool
   True when the state machine has stalled due to a full TX FIFO since the last clear_txstall call.

rxstall :bool
   True when the state machine has stalled due to a full RX FIFO since the last clear_rxfifo call.

in_waiting :int
   The number of words available to readinto

deinit() → None
   Turn off the state machine and release its resources.

   __enter__() → StateMachine
   No-op used by Context Managers. Provided by context manager helper.

   __exit__() → None
   Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

restart() → None
   Resets this state machine, runs any init and enables the clock.

run(instructions: circuitpython_typing.ReadableBuffer) → None
   Runs all given instructions. They will likely be interleaved with in-memory instructions. Make sure this doesn’t wait for input!

   This can be used to output internal state to the RX FIFO and then read with readinto.
**stop()** → None

Stops the state machine clock. Use **restart** to enable it.

**write**(buffer: `circuitpython_typing.ReadableBuffer`, *, start: int = 0, end: Optional[int] = None, swap: bool = False) → None

Write the data contained in `buffer` to the state machine. If the buffer is empty, nothing happens.

Writes to the FIFO will match the input buffer’s element size. For example, bytearray elements will perform 8 bit writes to the PIO FIFO. The RP2040’s memory bus will duplicate the value into the other byte positions. So, pulling more data in the PIO assembly will read the duplicated values.

To perform 16 or 32 bits writes into the FIFO use an `array.array` with a type code of the desired size.

**Parameters**

- **buffer** (`ReadableBuffer`) – Write out the data in this buffer
- **start** (`int`) – Start of the slice of `buffer` to write out: `buffer[start:end]`
- **end** (`int`) – End of the slice; this index is not included. Defaults to `len(buffer)`
- **swap** (`bool`) – For 2- and 4-byte elements, swap (reverse) the byte order

**background_write**(once: Optional[`circuitpython_typing.ReadableBuffer`] = None, *, loop: Optional[`circuitpython_typing.ReadableBuffer`] = None, swap: bool = False) → None

Write data to the TX fifo in the background, with optional looping.

First, if any previous **once** or **loop** buffer has not been started, this function blocks until they have. This means that any **once** or **loop** buffer will be written at least once. Then the **once** and/or **loop** buffers are queued and the function returns. The **once** buffer (if specified) will be written just once. Finally, the **loop** buffer (if specified) will continue being looped indefinitely.

Writes to the FIFO will match the input buffer’s element size. For example, bytearray elements will perform 8 bit writes to the PIO FIFO. The RP2040’s memory bus will duplicate the value into the other byte positions. So, pulling more data in the PIO assembly will read the duplicated values.

To perform 16 or 32 bits writes into the FIFO use an `array.array` with a type code of the desired size, or use `memoryview.cast` to change the interpretation of an existing buffer. To send just part of a larger buffer, slice a `memoryview` of it.

If a buffer is modified while it is being written out, the updated values will be used. However, because of interactions between CPU writes, DMA and the PIO FIFO are complex, it is difficult to predict the result of modifying multiple values. Instead, alternate between a pair of buffers.

Having both a **once** and a **loop** parameter is to support a special case in PWM generation where a change in duty cycle requires a special transitional buffer to be used exactly once. Most use cases will probably only use one of **once** or **loop**.

Having neither **once** nor **loop** terminates an existing background looping write after exactly a whole loop. This is in contrast to **stop_background_write**, which interrupts an ongoing DMA operation.

**Parameters**

- **once** (~`Optional[circuitpython_typing.ReadableBuffer]`) – Data to be written once
- **loop** (~`Optional[circuitpython_typing.ReadableBuffer]`) – Data to be written repeatedly
- **swap** (`bool`) – For 2- and 4-byte elements, swap (reverse) the byte order
stop_background_write() → None
Immediately stop a background write, if one is in progress. Any DMA in progress is halted, but items
already in the TX FIFO are not affected.

readinto(buffer: circuitpython_typing.WriteableBuffer, *, start: int = 0, end: Optional[int] = None, swap: bool = False) → None
Read into buffer. If the number of bytes to read is 0, nothing happens. The buffer includes any data added
to the fifo even if it was added before this was called.

Reads from the FIFO will match the input buffer’s element size. For example, bytearray elements will per-
form 8 bit reads from the PIO FIFO. The alignment within the 32 bit value depends on in_shift_right.
When in_shift_right is True, the upper N bits will be read. The lower bits will be read when
in_shift_right is False.

To perform 16 or 32 bits writes into the FIFO use an array.array with a type code of the desired size.

Parameters
- buffer (WriteableBuffer) – Read data into this buffer
- start (int) – Start of the slice of buffer to read into: buffer[start:end]
- end (int) – End of the slice; this index is not included. Defaults to len(buffer)
- swap (bool) – For 2- and 4-byte elements, swap (reverse) the byte order

write_readinto(buffer_out: circuitpython_typing.ReadableBuffer, buffer_in: circuitpython_typing.WriteableBuffer, *, out_start: int = 0, out_end: Optional[int] = None, in_start: int = 0, in_end: Optional[int] = None) → None
Write out the data in buffer_out while simultaneously reading data into buffer_in. The lengths of
the slices defined by buffer_out[out_start:out_end] and buffer_in[in_start:in_end] may be
different. The function will return once both are filled. If buffer slice lengths are both 0, nothing happens.

Data transfers to and from the FIFOs will match the corresponding buffer’s element size. See write and
readinto for details.

To perform 16 or 32 bits writes into the FIFO use an array.array with a type code of the desired size.

Parameters
- buffer_out (ReadableBuffer) – Write out the data in this buffer
- buffer_in (WriteableBuffer) – Read data into this buffer
- out_start (int) – Start of the slice of buffer_out to write out: buffer_out[out_start:out_end]
- out_end (int) – End of the slice; this index is not included. Defaults to len(buffer_out)
- in_start (int) – Start of the slice of buffer_in to read into: buffer_in[in_start:in_end]
- in_end (int) – End of the slice; this index is not included. Defaults to len(buffer_in)
- swap_out (bool) – For 2- and 4-byte elements, swap (reverse) the byte order for the buffer
  being transmitted (written)
- swap_in (bool) – For 2- and 4-rx elements, swap (reverse) the byte order for the buffer
  being received (read)

clear_rxfifo() → None
Clears any unread bytes in the rxfifo.
clear_txstall() → None

Clears the txstall flag.

**rtc – Real Time Clock**

The `rtc` module provides support for a Real Time Clock. You can access and manage the RTC using `rtc.RTC`. It also backs the `time.time()` and `time.localtime()` functions using the onboard RTC if present.

**rtc.set_time_source(rtc: RTC) → None**

Sets the RTC time source used by `time.localtime()`. The default is `rtc.RTC`, but it’s useful to use this to override the time source for testing purposes. For example:

```python
import rtc
import time

class RTC(object):
    @property
def datetime(self):
        return time.struct_time((2018, 3, 17, 21, 1, 47, 0, 0, 0))

r = RTC()
rtc.set_time_source(r)
```

**class rtc.RTC**

Real Time Clock

This class represents the onboard Real Time Clock. It is a singleton and will always return the same instance.

**datetime :time.struct_time**

The current date and time of the RTC as a `time.struct_time`. This must be set to the current date and time whenever the board loses power:

```python
import rtc
import time

r = rtc.RTC()
r.datetime = time.struct_time((2019, 5, 29, 15, 14, 15, 0, -1, -1))
```

Once set, the RTC will automatically update this value as time passes. You can read this property to get a snapshot of the current time:

```python
current_time = r.datetime
print(current_time)
# struct_time(tm_year=2019, tm_month=5, ...)```

**calibration :int**

The RTC calibration value as an `int`. A positive value speeds up the clock and a negative value slows it down.

**Limitations:** Calibration not supported on SAMD, nRF, RP240, Spresense, and STM.

Range and value is hardware specific, but one step is often approximately 1 ppm:
```python
import rtc
import time

r = rtc.RTC()
r.calibration = 1
```

---

**samd – SAMD implementation settings**

```python
class samd.Clock

Identifies a clock on the microcontroller.

They are fixed by the hardware so they cannot be constructed on demand. Instead, use `samd.clock` to reference the desired clock.

**enabled : bool**

Is the clock enabled? (read-only)

**parent : Union[Clock, None]**

Clock parent. (read-only)

**frequency : int**

Clock frequency in Herz. (read-only)

**calibration : int**

Clock calibration. Not all clocks can be calibrated.
```

---

**sdcardio – Interface to an SD card via the SPI bus**

```python
class sdcardio.SDCard(bus: busio.SPI, cs: microcontroller.Pin, baudrate: int = 8000000)

SD Card Block Interface

Controls an SD card over SPI. This built-in module has higher read performance than the library adafruit_sdcard, but it is only compatible with `busio.SPI`, not `bitbangio.SPI`. Usually an SDCard object is used with `storage.VfsFat` to allow file I/O to an SD card.

Construct an SPI SD Card object with the given properties

**Parameters**

- **spi (busio.SPI)** – The SPI bus
- **cs (microcontroller.Pin)** – The chip select connected to the card
- **baudrate (int)** – The SPI data rate to use after card setup

Note that during detection and configuration, a hard-coded low baudrate is used. Data transfers use the specified baudrate (rounded down to one that is supported by the microcontroller)

**Important**: If the same SPI bus is shared with other peripherals, it is important that the SD card be initialized before accessing any other peripheral on the bus. Failure to do so can prevent the SD card from being recognized until it is powered off or re-inserted.
```

Example usage:
Import os
import board
import sdcardio
import storage

sd = sdcardio.SDCard(board.SPI(), board.SD_CS)
vfs = storage.VfsFat(sd)
storage.mount(vfs, '/sd')
os.listdir('/sd')

count() \rightarrow int
Returns the total number of sectors

Due to technical limitations, this is a function and not a property.

Returns
The number of 512-byte blocks, as a number

definit() \rightarrow None
Disable permanently.

Returns
None

readblocks(start_block: int, buf: circuitpython_typing.WriteableBuffer) \rightarrow None
Read one or more blocks from the card

Parameters
- start_block (int) – The block to start reading from
- buf (WriteableBuffer) – The buffer to write into. Length must be multiple of 512.

Returns
None

sync() \rightarrow None
Ensure all blocks written are actually committed to the SD card

Returns
None

writeblocks(start_block: int, buf: circuitpython_typing.ReadableBuffer) \rightarrow None
Write one or more blocks to the card

Parameters
- start_block (int) – The block to start writing from
- buf (ReadableBuffer) – The buffer to read from. Length must be multiple of 512.

Returns
None
sdioio – Interface to an SD card via the SDIO bus

class sdioio.SDCard(clock: microcontroller.Pin, command: microcontroller.Pin, data: Sequence[microcontroller.Pin], frequency: int)

SD Card Block Interface with SDIO

Controls an SD card over SDIO. SDIO is a parallel protocol designed for SD cards. It uses a clock pin, a command pin, and 1 or 4 data pins. It can be operated at a high frequency such as 25MHz. Usually an SDCard object is used with storage.VfsFat to allow file I/O to an SD card.

Construct an SDIO SD Card object with the given properties

Parameters

- **clock** *(Pin)* – the pin to use for the clock.
- **command** *(Pin)* – the pin to use for the command.
- **data** – A sequence of pins to use for data.
- **frequency** – The frequency of the bus in Hz

Example usage:

```python
import os
import board
import sdioio
import storage

sd = sdioio.SDCard(
    clock=board.SDIO_CLOCK,
    command=board.SDIO_COMMAND,
    data=board.SDIO_DATA,
    frequency=25000000)

vfs = storage.VfsFat(sd)
storage.mount(vfs, '/sd')
os.listdir('/sd')
```

**frequency** : int
The actual SDIO bus frequency. This may not match the frequency requested due to internal limitations.

**width** : int
The actual SDIO bus width, in bits

**configure**(frequency: int = 0, width: int = 0) → None
Configures the SDIO bus.

Parameters

- **frequency** *(int)* – the desired clock rate in Hertz. The actual clock rate may be higher or lower due to the granularity of available clock settings. Check the frequency attribute for the actual clock rate.
- **width** *(int)* – the number of data lines to use. Must be 1 or 4 and must also not exceed the number of data lines at construction

**Note:** Leaving a value unspecified or 0 means the current setting is kept.
count() → int
Returns the total number of sectors
Due to technical limitations, this is a function and not a property.

Returns
The number of 512-byte blocks, as a number

readblocks(start_block: int, buf: circuitpython_typing.WriteableBuffer) → None
Read one or more blocks from the card

Parameters
• start_block (int) – The block to start reading from
• buf (WriteableBuffer) – The buffer to write into. Length must be multiple of 512.

Returns
None

writeblocks(start_block: int, buf: circuitpython_typing.ReadableBuffer) → None
Write one or more blocks to the card

Parameters
• start_block (int) – The block to start writing from
• buf (ReadableBuffer) – The buffer to read from. Length must be multiple of 512.

Returns
None

deinit() → None
Disable permanently.

__enter__() → SDCard
No-op used by Context Managers. Provided by context manager helper.

__exit__() → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

sharpdisplay – Support for Sharp Memory Display framebuffers
For more information about working with Sharp Memory Displays, see this Learn guide.

socketpool
The socketpool module provides sockets through a pool. The pools themselves act like CPython’s socket module.
For more information about the socket module, see the CPython documentation: https://docs.python.org/3/library/socket.html
class socketpool.Socket

TCP, UDP and RAW socket. Cannot be created directly. Instead, call `SocketPool.socket()`.

Provides a subset of CPython’s `socket.socket` API. It only implements the versions of `recv` that do not allocate bytes objects.

**__hash__()** → int

Returns a hash for the Socket.

**__enter__()** → Socket

No-op used by Context Managers.

**__exit__()** → None

Automatically closes the Socket when exiting a context. See `Lifetime and ContextManagers` for more info.

**accept()** → Tuple[Socket, Tuple[str, int]]

Accept a connection on a listening socket of type SOCK_STREAM, creating a new socket of type SOCK_STREAM. Returns a tuple of (new_socket, remote_address)

**bind(address: Tuple[str, int])** → None

Bind a socket to an address

Parameters

- **address** (~tuple) – tuple of (remote_address, remote_port)

**close()** → None

Closes this Socket and makes its resources available to its SocketPool.

**connect(address: Tuple[str, int])** → None

Connect a socket to a remote address

Parameters

- **address** (~tuple) – tuple of (remote_address, remote_port)

**listen(backlog: int)** → None

Set socket to listen for incoming connections

Parameters

- **backlog** (~int) – length of backlog queue for waiting connections

**recvfrom_into(buffer: circuitpython_typing.WriteableBuffer)** → Tuple[int, Tuple[str, int]]

Reads some bytes from a remote address.

Returns a tuple containing * the number of bytes received into the given buffer * a remote_address, which is a tuple of ip address and port number

Parameters

- **buffer** (object) – buffer to read into

**recv_into(buffer: circuitpython_typing.WriteableBuffer, bufsize: int)** → int

Reads some bytes from the connected remote address, writing into the provided buffer. If bufsize <= len(buffer) is given, a maximum of bufsize bytes will be read into the buffer. If no valid value is given for bufsize, the default is the length of the given buffer.

Suits sockets of type SOCK_STREAM Returns an int of number of bytes read.

Parameters

- **buffer** (bytearray) – buffer to receive into
- **bufsize** (int) – optionally, a maximum number of bytes to read.
send(bytes: circuitpython_typing.ReadableBuffer) → int
Send some bytes to the connected remote address. Suits sockets of type SOCK_STREAM

Parameters
bytes (~bytes) – some bytes to send

sendall(bytes: circuitpython_typing.ReadableBuffer) → None
Send some bytes to the connected remote address. Suits sockets of type SOCK_STREAM
This calls send() repeatedly until all the data is sent or an error occurs. If an error occurs, it's impossible to tell how much data has been sent.

Parameters
bytes (~bytes) – some bytes to send

sendto(bytes: circuitpython_typing.ReadableBuffer, address: Tuple[str, int]) → int
Send some bytes to a specific address. Suits sockets of type SOCK_DGRAM

Parameters
• bytes (~bytes) – some bytes to send
• address (~tuple) – tuple of (remote_address, remote_port)

setblocking(flag: bool) → Optional[int]
Set the blocking behaviour of this socket.

Parameters
flag (~bool) – False means non-blocking, True means block indefinitely.

settimeout(value: int) → None
Set the timeout value for this socket.

Parameters
value (~int) – timeout in seconds. 0 means non-blocking. None means block indefinitely.

class socketpool.SocketPool(radio: wifi.Radio)
A pool of socket resources available for the given radio. Only one SocketPool can be created for each radio.
SocketPool should be used in place of CPython's socket which provides a pool of sockets provided by the underlying OS.

Create a new SocketPool object for the provided radio

Parameters
radio (wifi.Radio) – The (connected) network hardware to associate with this SocketPool; currently, this will always be the object returned by wifi.radio

AF_INET :int
AF_INET6 :int
SOCK_STREAM :int
SOCK_DGRAM :int
SOCK_RAW :int

socket(family: int = AF_INET, type: int = SOCK_STREAM) → Socket
Create a new socket

Parameters
• **family (~int)** – AF_INET or AF_INET6
• **type (~int)** – SOCK_STREAM, SOCK_DGRAM or SOCK_RAW

The `proto` (protocol) and `fileno` arguments available in `socket.socket()` in CPython are not supported.

`getaddrinfo**(host: str, port: int, family: int = 0, type: int = 0, proto: int = 0, flags: int = 0)** → Tuple[int, int, int, str, Tuple[str, int]]

Gets the address information for a hostname and port

Returns the appropriate family, socket type, socket protocol and address information to call `socket.socket()` and `socket.connect()` with, as a tuple.

### ssl

The `ssl` module provides SSL contexts to wrap sockets in.

*This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: `ssl`.*

`ssl.create_default_context()` → `SSLContext`

Return the default SSLContext.

**class ssl.SSLContext**

Settings related to SSL that can be applied to a socket by wrapping it. This is useful to provide SSL certificates to specific connections rather than all of them.

- **check_hostname :bool**
  Whether to match the peer certificate’s hostname.

- **load_cert_chain**(certfile: str, keyfile: str) → None
  Load a private key and the corresponding certificate.
  The certfile string must be the path to a single file in PEM format containing the certificate as well as any number of CA certificates needed to establish the certificate’s authenticity. The keyfile string must point to a file containing the private key.

- **load_verify_locations**(cafile: Optional[str] = None) → None
  Load a set of certification authority (CA) certificates used to validate other peers’ certificates.

- **set_default_verify_paths**() → None
  Load a set of default certification authority (CA) certificates.

  Wraps the socket into a socket-compatible class that handles SSL negotiation. The socket must be of type SOCK_STREAM.

**class ssl.SSLSocket**

Implements TLS security on a subset of `socketpool.Socket` functions. Cannot be created directly. Instead, call `wrap_socket` on an existing socket object.

Provides a subset of CPython’s `ssl.SSLSocket` API. It only implements the versions of `recv` that do not allocate bytes objects.

- **__hash__()** → int
  Returns a hash for the Socket.
__enter__() → SSLSocket
No-op used by Context Managers.

__exit__() → None
Automatically closes the Socket when exiting a context. See *Lifetime and ContextManagers* for more info.

accept() → Tuple[SSLSocket, Tuple[str, int]]
Accept a connection on a listening socket of type SOCK_STREAM, creating a new socket of type SOCK_STREAM. Returns a tuple of (new_socket, remote_address)

bind(address: Tuple[str, int]) → None
Bind a socket to an address

Parameters
address (~tuple) – tuple of (remote_address, remote_port)

close() → None
Closes this Socket

connect(address: Tuple[str, int]) → None
Connect a socket to a remote address

Parameters
address (~tuple) – tuple of (remote_address, remote_port)

listen(backlog: int) → None
Set socket to listen for incoming connections

Parameters
backlog (~int) – length of backlog queue for waiting connections

recv_into(buffer: circuitpython_typing.WriteableBuffer, bufsize: int) → int
Reads some bytes from the connected remote address, writing into the provided buffer. If bufsize \(\leq\) len(buffer) is given, a maximum of bufsize bytes will be read into the buffer. If no valid value is given for bufsize, the default is the length of the given buffer.

Suits sockets of type SOCK_STREAM Returns an int of number of bytes read.

Parameters
• buffer (bytearray) – buffer to receive into
• bufsize (int) – optionally, a maximum number of bytes to read.

send(bytes: circuitpython_typing.ReadableBuffer) → int
Send some bytes to the connected remote address. Suits sockets of type SOCK_STREAM

Parameters
bytes (~bytes) – some bytes to send

settimeout(value: int) → None
Set the timeout value for this socket.

Parameters
value (~int) – timeout in seconds. 0 means non-blocking. None means block indefinitely.

setblocking(flag: bool) → Optional[int]
Set the blocking behaviour of this socket.

Parameters
flag (~bool) – False means non-blocking, True means block indefinitely.
storage – Storage management

The storage provides storage management functionality such as mounting and unmounting which is typically handled by the operating system hosting Python. CircuitPython does not have an OS, so this module provides this functionality directly.

For more information regarding using the storage module, refer to the CircuitPython Essentials Learn guide.

`storage.mount(filesystem: VfsFat, mount_path: str, *, readonly: bool = False) → None`

Mounts the given filesystem object at the given path.

This is the CircuitPython analog to the UNIX mount command.

**Parameters**

- **filesystem (VfsFat)** – The filesystem to mount.
- **mount_path (str)** – Where to mount the filesystem.
- **readonly (bool)** – True when the filesystem should be readonly to CircuitPython.

`storage.umount(mount: Union[str, VfsFat]) → None`

Unmounts the given filesystem object or if mount is a path, then unmount the filesystem mounted at that location.

This is the CircuitPython analog to the UNIX umount command.

`storage.remount(mount_path: str, readonly: bool = False, *, disable_concurrent_write_protection: bool = False) → None`

Remounts the given path with new parameters.

**Parameters**

- **mount_path (str)** – The path to remount.
- **readonly (bool)** – True when the filesystem should be readonly to CircuitPython.
- **disable_concurrent_write_protection (bool)** – When True, the check that makes sure the underlying filesystem data is written by one computer is disabled. Disabling the protection allows CircuitPython and a host to write to the same filesystem with the risk that the filesystem will be corrupted.

`storage.getmount(mount_path: str) → VfsFat`

Retrieves the mount object associated with the mount path.

`storage.erase_filesystem(extended: Optional[bool] = None) → None`

Erase and re-create the CIRCUITPY filesystem.

On boards that present USB-visible CIRCUITPY drive (e.g., SAMD21 and SAMD51), then call `microcontroller.reset()` to restart CircuitPython and have the host computer remount CIRCUITPY.

This function can be called from the REPL when CIRCUITPY has become corrupted.

**Parameters**

- **extended (bool)** – On boards that support dualbank module and the extended parameter, the CIRCUITPY storage can be extended by setting this to True. If this isn’t provided or set to None (default), the existing configuration will be used.

**Warning:** All the data on CIRCUITPY will be lost, and CircuitPython will restart on certain boards.
storage.disable_usb_drive() → None

Disable presenting CIRCUITPY as a USB mass storage device. By default, the device is enabled and CIRCUITPY is visible. Can be called in boot.py, before USB is connected.

storage.enable_usb_drive() → None

Enabled presenting CIRCUITPY as a USB mass storage device. By default, the device is enabled and CIRCUITPY is visible, so you do not normally need to call this function. Can be called in boot.py, before USB is connected.

If you enable too many devices at once, you will run out of USB endpoints. The number of available endpoints varies by microcontroller. CircuitPython will go into safe mode after running boot.py to inform you if not enough endpoints are available.

class storage.VfsFat(block_device: str)

Create a new VfsFat filesystem around the given block device.

    Parameters
    block_device – Block device the filesystem lives on

    label : str
        The filesystem label, up to 11 case-insensitive bytes. Note that this property can only be set when the device is writable by the microcontroller.

mkfs() → None

Format the block device, deleting any data that may have been there

open(path: str, mode: str) → None

Like builtin open()

ilistdir(path: str) → Iterator[Union[Tuple[AnyStr, int, int, int], Tuple[AnyStr, int, int]]]

Return an iterator whose values describe files and folders within path

mkdir(path: str) → None

Like os.mkdir

rmdir(path: str) → None

Like os.rmdir

stat(path: str) → Tuple[int, int, int, int, int, int, int, int, int, int]

Like os.stat

statvfs(path: int) → Tuple[int, int, int, int, int, int, int, int, int, int]

Like os.statvfs

mount(readonly: bool, mkfs: VfsFat) → None

Don’t call this directly, call storage.mount.

umount() → None

Don’t call this directly, call storage.umount.
struct – Manipulation of c-style data

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: struct.

Supported size/byte order prefixes: @, <, >, !.

Supported format codes: b, B, x, h, H, i, I, l, L, q, Q, s, p, f, d (the latter 2 depending on the floating-point support).

struct.calcsize(fmt: str) → int
Return the number of bytes needed to store the given fmt.

struct.pack(fmt: str, *values: Any) → bytes
Pack the values according to the format string fmt. The return value is a bytes object encoding the values.

struct.pack_into(fmt: str, buffer: circuitpython_typing.WriteableBuffer, offset: int, *values: Any) → None
Pack the values according to the format string fmt into a buffer starting at offset. offset may be negative to count from the end of buffer.

struct.unpack(fmt: str, data: circuitpython_typing.ReadableBuffer) → Tuple[Any, Ellipsis]
Unpack from the data according to the format string fmt. The return value is a tuple of the unpacked values. The buffer size must match the size required by the format.

struct.unpack_from(fmt: str, data: circuitpython_typing.ReadableBuffer, offset: int = 0) → Tuple[Any, Ellipsis]
Unpack from the data starting at offset according to the format string fmt. offset may be negative to count from the end of buffer. The return value is a tuple of the unpacked values. The buffer size must be at least as big as the size required by the form.

supervisor – Supervisor settings

supervisor.runtime :Runtime
Runtime information, such as runtime.serial_connected (USB serial connection status). This object is the sole instance of supervisor.Runtime.

supervisor.status_bar :StatusBar
The status bar, shown on an attached display, and also sent to an attached terminal via OSC escape codes over the REPL serial connection. The status bar reports the current IP or BLE connection, what file is running, the last exception name and location, and firmware version information. This object is the sole instance of supervisor.StatusBar.

supervisor.reload() → None
Reload the main Python code and run it (equivalent to hitting Ctrl-D at the REPL).

Set what file to run on the next vm run.

When not None, the given filename is inserted at the front of the usual ['code.py', 'main.py'] search sequence. The optional keyword arguments specify what happens after the specified file has run:

sticky_on_... determine whether the newly set filename and options stay in effect: If True, further runs will continue to run that file (unless it says otherwise by calling set_next_code_filename() itself). If False, the settings will only affect one run and revert to the standard code.py/main.py afterwards.
reload_on_... determine how to continue: If False, wait in the usual “Code done running. Waiting for reload. Press any key to enter the REPL. Use CTRL-D to reload.” state. If True, reload immediately as if CTRL-D was pressed.

..._on_success take effect when the program runs to completion or calls sys.exit().

..._on_error take effect when the program exits with an exception, including the KeyboardInterrupt caused by CTRL-C.

..._on_reload take effect when the program is interrupted by files being written to the USB drive (auto-reload) or when it calls supervisor.reload().

These settings are stored in RAM, not in persistent memory, and will therefore only affect soft reloads. Powering off or resetting the device will always revert to standard settings.

When called multiple times in the same run, only the last call takes effect, replacing any settings made by previous ones. This is the main use of passing None as a filename: to reset to the standard search sequence.

supervisor.ticks_ms() → int

Return the time in milliseconds since an unspecified reference point, wrapping after 2**29ms.

The value is initialized so that the first overflow occurs about 65 seconds after power-on, making it feasible to check that your program works properly around an overflow.

The wrap value was chosen so that it is always possible to add or subtract two ticks_ms values without overflow on a board without long ints (or without allocating any long integer objects, on boards with long ints).

This ticks value comes from a low-accuracy clock internal to the microcontroller, just like time.monotonic. Due to its low accuracy and the fact that it “wraps around” every few days, it is intended for working with short term events like advancing an LED animation, not for long term events like counting down the time until a holiday.

Addition, subtraction, and comparison of ticks values can be done with routines like the following:

```python
_TICKS_PERIOD = const(1<<29)
_TICKS_MAX = const(_TICKS_PERIOD-1)
_TICKS_HALFPERIOD = const(_TICKS_PERIOD//2)

def ticks_add(ticks, delta):
    """Add a delta to a base number of ticks, performing wraparound at 2**29ms."""
    return (a + b) % _TICKS_PERIOD

de...  

supervisor.get_previous_traceback() → Optional[str]

If the last vm run ended with an exception (including the KeyboardInterrupt caused by CTRL-C), returns the traceback as a string. Otherwise, returns None.

An exception traceback is only preserved over a soft reload, a hard reset clears it.

1.8. Full Table of Contents
Only code (main or boot) runs are considered, not REPL runs.

```python
supervisor.reset_terminal(x_pixels: int, y_pixels: int) → None
```
Reset the CircuitPython serial terminal with new dimensions.

```python
supervisor.set_usb_identification(manufacturer: Optional[str] = None, product: Optional[str] = None, vid: int = -1, pid: int = -1) → None
```
Override identification constants in the USB Device Descriptor.

If passed, `manufacturer` and `product` must be ASCII strings (or buffers) of at most 126 characters. Any omitted arguments will be left at their default values.

This method must be called in boot.py to have any effect.

Not available on boards without native USB support.

```python
class supervisor.RunReason

The reason that CircuitPython started running.

STARTUP :object
    CircuitPython started the microcontroller started up. See `microcontroller.Processor.reset_reason` for more detail on why the microcontroller was started.

AUTO_RELOAD :object
    CircuitPython restarted due to an external write to the filesystem.

SUPERVISOR_RELOAD :object
    CircuitPython restarted due to a call to `supervisor.reload()`.

REPL_RELOAD :object
    CircuitPython started due to the user typing CTRL-D in the REPL.
```

```python
class supervisor.Runtime

Current status of runtime objects.

Usage:

```python
import supervisor
if supervisor.runtime.serial_connected:
    print("Hello World!")
```

You cannot create an instance of `supervisor.Runtime`. Use `supervisor.runtime` to access the sole instance available.

```python
usb_connected :bool
    Returns the USB enumeration status (read-only).

serial_connected :bool
    Returns the USB serial communication status (read-only).

serial_bytes_available :int
    Returns the whether any bytes are available to read on the USB serial input. Allows for polling to see whether to call the built-in input() or wait. (read-only)

run_reason :RunReason
    Why CircuitPython started running this particular time.

autoreload :bool
    Whether CircuitPython may autoreload based on workflow writes to the filesystem.
```
ble_workflow :bool
Enable/Disable ble workflow until a reset. This prevents BLE advertising outside of the VM and the services
used for it.

next_stack_limit :int
The size of the stack for the next vm run. If its too large, the default will be used.

rgb_status_brightness :int
Set brightness of status RGB LED from 0-255. This will take effect after the current code finishes and the
status LED is used to show the finish state.

class supervisor.StatusBar
Current status of runtime objects.
Usage:

```
import supervisor

supervisor.status_bar.console = False
```

You cannot create an instance of supervisor.StatusBar. Use supervisor.status_bar to access the sole
instance available.

console :bool
Whether status bar information is sent over the console (REPL) serial connection, using OSC terminal
escape codes that change the terminal’s title. Default is True. If set to False, status bar will be cleared
and then disabled. May be set in boot.py or later. Persists across soft restarts.

display :bool
Whether status bar information is displayed on the top line of the display. Default is True. If set to False,
status bar will be cleared and then disabled. May be set in boot.py or later. Persists across soft restarts.
Not available if terminalio is not available.

synthio – Support for MIDI synthesis

```
synthio.from_file(file: BinaryIO, *, sample_rate: int = 11025) → MidiTrack
```
Create an AudioSample from an already opened MIDI file. Currently, only single-track MIDI (type 0) is sup-
ported.

Parameters

- **file (BinaryIO)** – Already opened MIDI file
- **sample_rate (int)** – The desired playback sample rate; higher sample rate requires more
  memory

Playing a MIDI file from flash:

```
import audioio
import board
import synthio

data = open("single-track.midi", "rb")
midi = synthio.from_file(data)
a = audioio.AudioOut(board.A0)
```

(continues on next page)
```python
print("playing")
a.play(midi)
while a.playing:
  pass
print("stopped")
```

class synthio.MidiTrack(buffer: circuitpython_typing.ReadableBuffer, tempo: int, *, sample_rate: int = 11025)

Simple square-wave MIDI synth

Create a MidiTrack from the given stream of MIDI events. Only “Note On” and “Note Off” events are supported; channel numbers and key velocities are ignored. Up to two notes may be on at the same time.

Parameters

- **buffer** *(ReadableBuffer)* – Stream of MIDI events, as stored in a MIDI file track chunk
- **tempo** *(int)* – Tempo of the streamed events, in MIDI ticks per second
- **sample_rate** *(int)* – The desired playback sample rate; higher sample rate requires more memory

Simple melody:

```python
import audioio
import board
import synthio

dac = audioio.AudioOut(board.SPEAKER)
melody = synthio.MidiTrack(b"\x90\x90\x80\x80\x90\x90\x80\x80\x90\x90\x80\x80\x90\x90\x80\x80\x90\x90", tempo=640)
dac.play(melody)
print("playing")
while dac.playing:
  pass
print("stopped")
```

**sample_rate**: Optional[int]

32 bit value that tells how quickly samples are played in Hertz (cycles per second).

**deinit()** → None

Deinitialises the MidiTrack and releases any hardware resources for reuse.

**__enter__**() → MidiTrack

No-op used by Context Managers.

**__exit__**() → None

Automatically deinitializes the hardware when exiting a context. See *Lifetime and ContextManagers* for more info.
terminalio – Displays text in a TileGrid

The terminalio module contains classes to display a character stream on a display. The built in font is available as terminalio.FONT.

Note: This module does not give access to the REPL.

terminalio.FONT : fontio.BuiltinFont
The built in font

Display a character stream with a TileGrid

ASCII control: * - Move cursor to column 1 *
\n - Move cursor down a row *
\b - Move cursor left one if possible

OSC control sequences: * ESC ] 0; <s> ESC \ - Set title bar to <s> * ESC ] ###; <s> ESC \ - Ignored

VT100 control sequences: * ESC [ K - Clear the remainder of the line * ESC [ ### D - Move the cursor to the left by ### * ESC [ 2 J - Erase the entire display * ESC [ nnnn ; mmmm H - Move the cursor to mmmm, mnnn.

Terminal manages tile indices and cursor position based on VT100 commands. The font should be a fontio. BuiltinFont and the TileGrid’s bitmap should match the font’s bitmap.

write(buf: circuitpython_typing.ReadableBuffer) → Optional[int]
Write the buffer of bytes to the bus.

Returns
the number of bytes written

Return type
int or None

time – time and timing related functions

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: time.

time.monotonic() → float
Returns an always increasing value of time with an unknown reference point. Only use it to compare against other values from time.monotonic().

On most boards, time.monotonic() converts a 64-bit millisecond tick counter to a float. Floats on most boards are encoded in 30 bits internally, with effectively 22 bits of precision. The float returned by time.monotonic() will accurately represent time to millisecond precision only up to 2**22 milliseconds (about 1.165 hours). At that point it will start losing precision, and its value will change only every second millisecond. At 2**23 milliseconds it will change every fourth millisecond, and so forth.

If you need more consistent precision, use time.monotonic_ns() or supervisor.ticks_ms(). time.monotonic_ns() is not available on boards without long integer support. supervisor.ticks_ms() uses intervals of a millisecond, but wraps around, and is not CPython-compatible.

Returns
the current monotonic time
Return type
  float
time.sleep(seconds: float) → None
  Sleep for a given number of seconds.

Parameters
  seconds (float) – the time to sleep in fractional seconds

class time.struct_time(time_tuple: Sequence[int])
  Structure used to capture a date and time. Can be constructed from a struct_time, tuple, list, or namedtuple with 9 elements.

Parameters
  time_tuple (Sequence) – Sequence of time info: (tm_year, tm_mon, tm_mday, tm_hour, tm_min, tm_sec, tm_wday, tm_yday, tm_isdst)
  • tm_year: the year, 2017 for example
  • tm_mon: the month, range [1, 12]
  • tm_mday: the day of the month, range [1, 31]
  • tm_hour: the hour, range [0, 23]
  • tm_min: the minute, range [0, 59]
  • tm_sec: the second, range [0, 61]
  • tm_wday: the day of the week, range [0, 6], Monday is 0
  • tm_yday: the day of the year, range [1, 366], -1 indicates not known
  • tm_isdst: 1 when in daylight savings, 0 when not, -1 if unknown.

time.time() → int
  Return the current time in seconds since since Jan 1, 1970.

Returns
  the current time

Return type
  int
time.monotonic_ns() → int
  Return the time of the monotonic clock, which cannot go backward, in nanoseconds. Not available on boards without long integer support.

Returns
  the current time

Return type
  int
time.localtime(secs: int) → struct_time
  Convert a time expressed in seconds since Jan 1, 1970 to a struct_time in local time. If secs is not provided or None, the current time as returned by time() is used. The earliest date for which it can generate a time is Jan 1, 2000.

Returns
  the current time

Return type
  time.struct_time
The `touchio` module contains classes to provide access to touch IO typically accelerated by hardware on the onboard microcontroller.

All classes change hardware state and should be deinitialized when they are no longer needed if the program continues after use. To do so, either call `deinit()` or use a context manager. See *Lifetime and Context Managers* for more info.

For more information about working with the `touchio` module in CircuitPython, see the Learn guide page.

**Example:**

```python
import touchio
from board import *

touch_pin = touchio.TouchIn(D6)
print(touch_pin.value)
```

This example will initialize the device, and print the value.

**class** `touchio.TouchIn`(*pin: microcontroller.Pin*)

Read the state of a capacitive touch sensor

**Usage:**

```python
import touchio
from board import *

touch = touchio.TouchIn(A1)
while True:
    if touch.value:
        print("touched!")
```

Use the TouchIn on the given pin.

**Parameters**

- `pin` *(Pin)* – the pin to read from

**value** :bool

Whether the touch pad is being touched or not. (read-only)

- `raw_value` > `threshold`.

**raw_value** :int

The raw touch measurement as an `int`. (read-only)
threshold : Optional[int]

Minimum raw_value needed to detect a touch (and for value to be True).

When the TouchIn object is created, an initial raw_value is read from the pin, and then threshold is set to be 100 + that value.

You can adjust threshold to make the pin more or less sensitive:

```python
import board
import touchio
touch = touchio.TouchIn(board.A1)
touch.threshold = 7300
```

deinit() → None
Deinitialises the TouchIn and releases any hardware resources for reuse.

__enter__() → TouchIn
No-op used by Context Managers.

__exit__() → None
Automatically deinitializes the hardware when exiting a context. See Lifetime and ContextManagers for more info.

**traceback – Traceback Module**

This module provides a standard interface to print stack traces of programs. This is useful when you want to print stack traces under program control.

*This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: traceback.*

```python
```

Format a stack trace and the exception information.

If the exception value is passed in exc, then this exception value and its associated traceback are used. This is compatible with CPython 3.10 and newer.

If the exception value is passed in value, then any value passed in for exc is ignored. value is used as the exception value and the traceback in the tb argument is used. In this case, if tb is None, no traceback will be shown. This is compatible with CPython 3.5 and newer.

The arguments have the same meaning as the corresponding arguments to print_exception(). The return value is a list of strings, each ending in a newline and some containing internal newlines. When these lines are concatenated and printed, exactly the same text is printed as does print_exception().

**Note:** Setting chain will have no effect as chained exceptions are not yet implemented.

**Parameters**

- **exc** – The exception. Must be an instance of BaseException. Unused if value is specified.
- **value** – If specified, is used in place of exc.
• **tb** (*TracebackType*) – When value is also specified, `tb` is used in place of the exception’s own traceback. If `None`, the traceback will not be printed.

• **limit** (*int*) – Print up to limit stack trace entries (starting from the caller’s frame) if limit is positive. Otherwise, print the last `abs(limit)` entries. If limit is omitted or `None`, all entries are printed.

• **chain** (*bool*) – If `True` then chained exceptions will be printed (note: not yet implemented).

```python
```

Prints exception information and stack trace entries.

If the exception value is passed in `exc`, then this exception value and its associated traceback are used. This is compatible with CPython 3.10 and newer.

If the exception value is passed in `value`, then any value passed in for `exc` is ignored. `value` is used as the exception value and the traceback in the `tb` argument is used. In this case, if `tb` is `None`, no traceback will be shown. This is compatible with CPython 3.5 and newer.

---

**Note:** Setting `chain` will have no effect as chained exceptions are not yet implemented.

---

**Parameters**

- **exc** – The exception. Must be an instance of `BaseException`. Unused if value is specified.

- **value** – If specified, is used in place of `exc`.

- **tb** – When value is also specified, `tb` is used in place of the exception’s own traceback. If `None`, the traceback will not be printed.

- **limit** (*int*) – Print up to limit stack trace entries (starting from the caller’s frame) if limit is positive. Otherwise, print the last `abs(limit)` entries. If limit is omitted or `None`, all entries are printed.

- **file** (*io.FileIO*) – If file is omitted or `None`, the output goes to `sys.stderr`; otherwise it should be an open file or file-like object to receive the output.

- **chain** (*bool*) – If `True` then chained exceptions will be printed (note: not yet implemented).

---

**uheap – Heap size analysis**

```python
uheap.info(object: info.object) → int
```

Prints memory debugging info for the given object and returns the estimated size.
ulab – Manipulate numeric data similar to numpy

ulab is a numpy-like module for micropython, meant to simplify and speed up common mathematical operations on arrays. The primary goal was to implement a small subset of numpy that might be useful in the context of a microcontroller. This means low-level data processing of linear (array) and two-dimensional (matrix) data.

ulab is adapted from micropython-ulab, and the original project’s documentation can be found at https://micropython-ulab.readthedocs.io/en/latest/

ulab is modeled after numpy, and aims to be a compatible subset where possible. Numpy’s documentation can be found at https://docs.scipy.org/doc/numpy/index.html

ulab.numpy – Numerical approximation methods

ulab.numpy.carray – Return the real part of the complex argument, which can be either an ndarray, or a scalar.

ulab.numpy.carray.real(val)

ulab.numpy.carray.imag(val)

ulab.numpy.carray.conjugate(val)

ulab.numpy.carray.sort_complex(a: ulab.numpy.ndarray) → ulab.numpy.ndarray

Sort a complex array using the real part first, then the imaginary part. Always returns a sorted complex array, even if the input was real.

ulab.numpy.carray.abs(a: ulab.numpy.ndarray) → ulab.numpy.ndarray

Return the absolute value of complex ndarray.

ulab.numpy.fft – Frequency-domain functions

ulab.numpy.fft(r: ulab.numpy.ndarray, c: Optional[ulab.numpy.ndarray] = None) → Tuple[ulab.numpy.ndarray, ulab.numpy.ndarray]

Parameters

• r (ulab.numpy.ndarray) – A 1-dimension array of values whose size is a power of 2
• c (ulab.numpy.ndarray) – An optional 1-dimension array of values whose size is a power of 2, giving the complex part of the value

Return tuple (r, c)

The real and complex parts of the FFT

Perform a Fast Fourier Transform from the time domain into the frequency domain

See also ulab.utils.spectrogram, which computes the magnitude of the fft, rather than separately returning its real and imaginary parts.

ulab.numpy.fft.ifft(r: ulab.numpy.ndarray, c: Optional[ulab.numpy.ndarray] = None) → Tuple[ulab.numpy.ndarray, ulab.numpy.ndarray]

Parameters
• \texttt{r (ulab.numpy.ndarray)} – A 1-dimension array of values whose size is a power of 2
• \texttt{c (ulab.numpy.ndarray)} – An optional 1-dimension array of values whose size is a power of 2, giving the complex part of the value

Return tuple (r, c)

The real and complex parts of the inverse FFT

Perform an Inverse Fast Fourier Transform from the frequency domain into the time domain

\texttt{ulab.numpy.linalg}

\texttt{ulab.numpy.linalg.cholesky(A: ulab.numpy.ndarray) \rightarrow ulab.numpy.ndarray}

Parameters

\texttt{A (ndarray)} – a positive definite, symmetric square matrix

Return ~\texttt{ulab.numpy.ndarray L}

a square root matrix in the lower triangular form

Raises

\texttt{ValueError} – If the input does not fulfill the necessary conditions

The returned matrix satisfies the equation \texttt{m=LL^*}

\texttt{ulab.numpy.linalg.det(m: ulab.numpy.ndarray) \rightarrow float}

Param

\texttt{m, a square matrix}

Return float

The determinant of the matrix

Computes the eigenvalues and eigenvectors of a square matrix

\texttt{ulab.numpy.linalg.eig(m: ulab.numpy.ndarray) \rightarrow Tuple[ulab.numpy.ndarray, ulab.numpy.ndarray]}

Parameters

\texttt{m} – a square matrix

Return tuple (eigenvectors, eigenvalues)

Computes the eigenvalues and eigenvectors of a square matrix

\texttt{ulab.numpy.linalg.inv(m: ulab.numpy.ndarray) \rightarrow ulab.numpy.ndarray}

Parameters

\texttt{m (ndarray)} – a square matrix

Returns

The inverse of the matrix, if it exists

Raises

\texttt{ValueError} – if the matrix is not invertible

Computes the inverse of a square matrix

\texttt{ulab.numpy.linalg.norm(x: ulab.numpy.ndarray) \rightarrow float}

Parameters

\texttt{x (ndarray)} – a vector or a matrix

Computes the 2-norm of a vector or a matrix, i.e., \texttt{sqrt(sum(x^*x))}, however, without the RAM overhead.
ulab.numpy.linalg.qr(m: ulab.numpy.ndarray) → Tuple[ulab.numpy.ndarray, ulab.numpy.ndarray]

Parameters

m – a matrix

Return tuple (Q, R)

Factor the matrix a as QR, where Q is orthonormal and R is upper-triangular.


Parameters

• x (ulab.numpy.ndarray) – The x-coordinates at which to evaluate the interpolated values.
• xp (ulab.numpy.ndarray) – The x-coordinates of the data points, must be increasing
• fp (ulab.numpy.ndarray) – The y-coordinates of the data points, same length as xp
• left – Value to return for x < xp[0], default is fp[0].
• right – Value to return for x > xp[-1], default is fp[-1].

Returns the one-dimensional piecewise linear interpolant to a function with given discrete data points (xp, fp), evaluated at x.

ulab.numpy.trapz(y: ndarray, x: Optional[ndarray] = None, dx: _float = 1.0) → _float

Parameters

• y (1D ulab.numpy.ndarray) – the values of the dependent variable
• x (1D ulab.numpy.ndarray) – optional, the coordinates of the independent variable. Defaults to uniformly spaced values.
• dx (float) – the spacing between sample points, if x=None

Returns the integral of y(x) using the trapezoidal rule.

ulab.numpy.arange(stop: _float, step: _float = 1, *, dtype: _DType = ulab.numpy.float) → ndarray

ulab.numpy.arange(start: _float, stop: _float, step: _float = 1, *, dtype: _DType = ulab.numpy.float) → ndarray

Return a new 1-D array with elements ranging from start to stop, with step size step.

ulab.numpy.concatenate(arrays: Tuple[ndarray], *, axis: int = 0) → ndarray

Join a sequence of arrays along an existing axis.

ulab.numpy.diag(a: ndarray, *, k: int = 0) → ndarray

Return specified diagonals.

ulab.numpy.empty(shape: Union[int, Tuple[int, Ellipsis]], *, dtype: _DType = ulab.numpy.float) → ndarray

Return a new array of the given shape with all elements set to 0. An alias for numpy.zeros.

ulab.numpy.eye(size: int, *, M: Optional[int] = None, k: int = 0, dtype: _DType = ulab.numpy.float) → ndarray

Return a new square array of size, with the diagonal elements set to 1 and the other elements set to 0. If k is given, the diagonal is shifted by the specified amount.

ulab.numpy.full(shape: Union[int, Tuple[int, Ellipsis]], fill_value: Union[_float, _bool], *, dtype: _DType = ulab.numpy.float) → ndarray

Return a new array of the given shape with all elements set to 0.

Return a new 1-D array with num elements ranging from start to stop linearly.


Return a new 1-D array with num evenly spaced elements on a log scale. The sequence starts at base ** start, and ends with base ** stop.

ulab.numpy.ones(shape: Union[int, Tuple[int, Ellipsis]], *, dtype: _DType = ulab.numpy.float) → ndarray

Return a new array of the given shape with all elements set to 1.

ulab.numpy.zeros(shape: Union[int, Tuple[int, Ellipsis]], *, dtype: _DType = ulab.numpy.float) → ndarray

Return a new array of the given shape with all elements set to 0.

ulab.numpy._ArrayLike

ulab.numpy._DType

ulab.numpy.int8 : _DType

Type code for signed integers in the range -128 .. 127 inclusive, like the ‘b’ typecode of array.array

ulab.numpy.int16 : _DType

Type code for signed integers in the range -32768 .. 32767 inclusive, like the ‘h’ typecode of array.array

ulab.numpy.float : _DType

Type code for floating point values, like the ‘f’ typecode of array.array

ulab.numpy.uint8 : _DType

Type code for unsigned integers in the range 0 .. 255 inclusive, like the ‘H’ typecode of array.array

ulab.numpy.uint16 : _DType

Type code for unsigned integers in the range 0 .. 65535 inclusive, like the ‘h’ typecode of array.array

ulab.numpy.bool : _DType

Type code for boolean values

ulab.numpy.argmax(array: _ArrayLike, *, axis: Optional[int] = None) → int

Return the index of the maximum element of the 1D array

ulab.numpy.argmin(array: _ArrayLike, *, axis: Optional[int] = None) → int

Return the index of the minimum element of the 1D array

ulab.numpy.argsort(array: ndarray, *, axis: int = -1) → ndarray

Returns an array which gives indices into the input array from least to greatest.

ulab.numpy.cross(a: ndarray, b: ndarray) → ndarray

Return the cross product of two vectors of length 3

ulab.numpy.diff(array: ndarray, *, n: int = 1, axis: int = -1) → ndarray

Return the numerical derivative of successive elements of the array, as an array. axis=None is not supported.

ulab.numpy.flip(array: ndarray, *, axis: Optional[int] = None) → ndarray

Returns a new array that reverses the order of the elements along the given axis, or along all axes if axis is None.
ulab.numpy.max(array: _ArrayLike, *, axis: Optional[int] = None) → float
Return the maximum element of the 1D array

ulab.numpy.mean(array: _ArrayLike, *, axis: Optional[int] = None) → float
Return the mean element of the 1D array, as a number if axis is None, otherwise as an array.

ulab.numpy.median(array: ndarray, *, axis: int = -1) → ndarray
Find the median value in an array along the given axis, or along all axes if axis is None.

ulab.numpy.min(array: _ArrayLike, *, axis: Optional[int] = None) → float
Return the minimum element of the 1D array

ulab.numpy.roll(array: ndarray, distance: int, *, axis: Optional[int] = None) → None
Shift the content of a vector by the positions given as the second argument. If the axis keyword is supplied, the shift is applied to the given axis. The array is modified in place.

ulab.numpy.sort(array: ndarray, *, axis: int = -1) → ndarray
Sort the array along the given axis, or along all axes if axis is None. The array is modified in place.

ulab.numpy.std(array: _ArrayLike, *, axis: Optional[int] = None, ddof: int = 0) → float
Return the standard deviation of the array, as a number if axis is None, otherwise as an array.

ulab.numpy.sum(array: _ArrayLike, *, axis: Optional[int] = None) → Union[float, int, ndarray]
Return the sum of the array, as a number if axis is None, otherwise as an array.

class ulab.numpy.ndarray
ulab.numpy.get_printoptions() → Dict[str, int]
Get printing options

ulab.numpy.set_printoptions(threshold: Optional[int] = None, edgeitems: Optional[int] = None) → None
Set printing options

ulab.numpy.ndinfo(array: ndarray) → None
ulab.numpy.array(values: Union[ndarray, Iterable[Union[float, bool, Iterable[Any]]]], *, dtype: _DType = ulab.numpy.float) → ndarray
alternate constructor function for ulab.numpy.ndarray. Mirrors numpy.array

ulab.numpy.trace(m: ndarray) → float
Parameters
m – a square matrix

Compute the trace of the matrix, the sum of its diagonal elements.

ulab.numpy.dot(m1: ndarray, m2: ndarray) → Union[ndarray, float]
Parameters

• m1 (ndarray) – a matrix, or a vector
• m2 (ndarray) – a matrix, or a vector

Computes the product of two matrices, or two vectors. In the letter case, the inner product is returned.

ulab.numpy.acos(a: _ArrayLike) → ndarray
Computes the inverse cosine function
ulab.numpy.acosh(a: _ArrayLike) → ndarray
Computes the inverse hyperbolic cosine function

ulab.numpy.asin(a: _ArrayLike) → ndarray
Computes the inverse sine function

ulab.numpy.asinh(a: _ArrayLike) → ndarray
Computes the inverse hyperbolic sine function

ulab.numpy.around(a: _ArrayLike, *, decimals: int = 0) → ndarray
Returns a new float array in which each element is rounded to decimals places.

ulab.numpy.atan(a: _ArrayLike) → ndarray
Computes the inverse tangent function; the return values are in the range [-pi/2, pi/2].

ulab.numpy.arctan2(ya: _ArrayLike, xa: _ArrayLike) → ndarray
Computes the inverse tangent function of y/x; the return values are in the range [-pi, pi].

ulab.numpy.atanh(a: _ArrayLike) → ndarray
Computes the inverse hyperbolic tangent function

ulab.numpy.ceil(a: _ArrayLike) → ndarray
Rounds numbers up to the next whole number

ulab.numpy.cos(a: _ArrayLike) → ndarray
Computes the cosine function

ulab.numpy.cosh(a: _ArrayLike) → ndarray
Computes the hyperbolic cosine function

ulab.numpy.degrees(a: _ArrayLike) → ndarray
Converts angles from radians to degrees

ulab.numpy.erf(a: _ArrayLike) → ndarray
Computes the error function, which has applications in statistics

ulab.numpy.erfc(a: _ArrayLike) → ndarray
Computes the complementary error function, which has applications in statistics

ulab.numpy.exp(a: _ArrayLike) → ndarray
Computes the exponent function.

ulab.numpy.expm1(a: _ArrayLike) → ndarray
Computes $e^x-1$. In certain applications, using this function preserves numeric accuracy better than the exp function.

ulab.numpy.floor(a: _ArrayLike) → ndarray
Rounds numbers up to the next whole number

ulab.numpy.gamma(a: _ArrayLike) → ndarray
Computes the gamma function

ulab.numpy.lgamma(a: _ArrayLike) → ndarray
Computes the natural log of the gamma function

ulab.numpy.log(a: _ArrayLike) → ndarray
Computes the natural log
ulab.numpy.log10(a: _ArrayLike) → ndarray
Computes the log base 10

ulab.numpy.log2(a: _ArrayLike) → ndarray
Computes the log base 2

ulab.numpy.radians(a: _ArrayLike) → ndarray
Converts angles from degrees to radians

ulab.numpy.sin(a: _ArrayLike) → ndarray
Computes the sine function

ulab.numpy.sinh(a: _ArrayLike) → ndarray
Computes the hyperbolic sine

ulab.numpy.sqrt(a: _ArrayLike) → ndarray
Computes the square root

ulab.numpy.tan(a: _ArrayLike) → ndarray
Computes the tangent

ulab.numpy.tanh(a: _ArrayLike) → ndarray
Computes the hyperbolic tangent

ulab.numpy.vectorize(f: Union[Callable[[int], float], Callable[[float], float]], *, otypes: Optional[_DType] = None) → Callable[[_ArrayLike], ndarray]

Parameters
• f (callable) – The function to wrap
• otypes – List of array types that may be returned by the function. None is interpreted to mean the return value is float.

Wrap a Python function f so that it can be applied to arrays. The callable must return only values of the types specified by otypes, or the result is undefined.

ulab.scipy – Compatibility layer for scipy

ulab.scipy.linalg

ulab.scipy.linalg.solve_triangular(A: ulab.numpy.ndarray, b: ulab.numpy.ndarray, lower: bool) → ulab.numpy.ndarray

Parameters
• A (ndarray) – a matrix
• b (ndarray) – a vector
• lower (~bool) – if true, use only data contained in lower triangle of A, else use upper triangle of A

Returns
solution to the system A x = b. Shape of return matches b

Raises
• TypeError – if A and b are not of type ndarray and are not dense
• `ValueError` – if A is a singular matrix

Solve the equation \( A \times x = b \) for \( x \), assuming \( A \) is a triangular matrix

```python
ulab.scipy.linalg.cho_solve(L: ulab.numpy.ndarray, b: ulab.numpy.ndarray) \rightarrow ulab.numpy.ndarray
```

**Parameters**
- \( L \) (ndarray) – the lower triangular, Cholesky factorization of \( A \)
- \( b \) (ndarray) – right-hand-side vector \( b \)

**Returns**
- solution to the system \( A \times x = b \). Shape of return matches \( b \)

**Raises**
- `TypeError` – if \( L \) and \( b \) are not of type ndarray and are not dense

Solve the linear equations \( A \times x = b \), given the Cholesky factorization of \( A \) as input

```python
ulab.scipy.optimize
```

```python
ulab.scipy.optimize.bisect(fun: Callable[[float], float], a: float, b: float, *, xtol: float = 2.4e-07, maxiter: int = 100) \rightarrow float
```

**Parameters**
- \( f \) (callable) – The function to bisect
- \( a \) (float) – The left side of the interval
- \( b \) (float) – The right side of the interval
- \( xtol \) (float) – The tolerance value
- \( maxiter \) (float) – The maximum number of iterations to perform

Find a solution (zero) of the function \( f(x) \) on the interval \((a..b..)\) using the bisection method. The result is accurate to within \( xtol \) unless more than \( maxiter \) steps are required.

```python
ulab.scipy.optimize.fmin(fun: Callable[[float], float], x0: float, *, xtol: float = 2.4e-07, fatol: float = 2.4e-07, maxiter: int = 200) \rightarrow float
```

**Parameters**
- \( f \) (callable) – The function to bisect
- \( x0 \) (float) – The initial \( x \) value
- \( xtol \) (float) – The absolute tolerance value
- \( fatol \) (float) – The relative tolerance value

Find a minimum of the function \( f(x) \) using the downhill simplex method. The located \( x \) is within \( fxtol \) of the actual minimum, and \( f(x) \) is within \( fatol \) of the actual minimum unless more than \( maxiter \) steps are required.

```python
ulab.scipy.optimize.newton(fun: Callable[[float], float], x0: float, *, xtol: float = 2.4e-07, rtol: float = 0.0, maxiter: int = 50) \rightarrow float
```

**Parameters**
- \( f \) (callable) – The function to bisect
- \( x0 \) (float) – The initial \( x \) value
Find a solution (zero) of the function $f(x)$ using Newton’s Method. The result is accurate to within $x_{tol} \times r_{tol} \times |f(x)|$ unless more than $max_{iter}$ steps are required.

ulab.user – This module should hold arbitrary user-defined functions.

ulab.utils

ulab.utils.spectrogram($r: \text{ulab.numpy.ndarray}$) $\rightarrow \text{ulab.numpy.ndarray}$

Parameters:

$r$ (ulab.numpy.ndarray) – A 1-dimension array of values whose size is a power of 2

Computes the spectrum of the input signal. This is the absolute value of the (complex-valued) fft of the signal. This function is similar to scipy’s scipy.signal.welch https://docs.scipy.org/doc/scipy/reference/generated/scipy.signal.welch.html.

usb – PyUSB-compatible USB host API

The $usb$ is a subset of PyUSB that allows you to communicate to USB devices.

usb.core – USB Core

This is a subset of the PyUSB core module.

exception usb.core.USBError

Bases: OSError

Catchall exception for USB related errors.

Initialize self. See help(type(self)) for accurate signature.

exception usb.core.USBTimeoutError

Bases: USBError

Raised when a USB transfer times out.

Initialize self. See help(type(self)) for accurate signature.

usb.core.find($\text{find\_all: bool = False, } *, \text{idVendor: Optional[int] = None, idProduct: Optional[int] = None} \rightarrow \text{Device}$)

Find the first device that matches the given requirements or, if find_all is True, return a generator of all matching devices.

Returns None if no device matches.

class usb.core.Device

User code cannot create Device objects. Instead, get them from $usb.core.find$.

$idVendor : \text{int}$

The USB vendor ID of the device
idProduct :int
The USB product ID of the device

serial_number :str
The USB device’s serial number string.

product :str
The USB device’s product string.

manufacturer :str
The USB device’s manufacturer string.

write(endpoint: int, data: circuitpython_typing.ReadableBuffer, timeout: Optional[int] = None) → int
Write data to a specific endpoint on the device.

Parameters
• endpoint (int) – the bEndpointAddress you want to communicate with.
• data (ReadableBuffer) – the data to send
• timeout (int) – Time to wait specified in milliseconds. (Different from most CircuitPython!)

Returns
the number of bytes written

read(endpoint: int, size_or_buffer: array.array, timeout: Optional[int] = None) → int
Read data from the endpoint.

Parameters
• endpoint (int) – the bEndpointAddress you want to communicate with.
• size_or_buffer (array.array) – the array to read data into. PyUSB also allows size but CircuitPython only support array to force deliberate memory use.
• timeout (int) – Time to wait specified in milliseconds. (Different from most CircuitPython!)

Returns
the number of bytes read

ctrl_transfer(bmRequestType: int, bRequest: int, wValue: int = 0, wIndex: int = 0, data_or_wLength: Optional[array.array] = None, timeout: Optional[int] = None) → int
Do a control transfer on the endpoint 0. The parameters bmRequestType, bRequest, wValue and wIndex are the same of the USB Standard Control Request format.

Control requests may or may not have a data payload to write/read. In cases which it has, the direction bit of the bmRequestType field is used to infer the desired request direction.

For host to device requests (OUT), data_or_wLength parameter is the data payload to send, and it must be a sequence type convertible to an array object. In this case, the return value is the number of bytes written in the data payload.

For device to host requests (IN), data_or_wLength is an array object which the data will be read to, and the return value is the number of bytes read.

is_kernel_driver_active(interface: int) → bool
Determine if CircuitPython is using the interface. If it is, the object will be unable to perform I/O.

Parameters
• interface (int) – the device interface number to check
**detach_kernel_driver** *(interface: int) → None*

Stop CircuitPython from using the interface. If successful, you will then be able to perform I/O. CircuitPython will automatically re-start using the interface on reload.

**Parameters**
- **interface** *(int)* – the device interface number to stop CircuitPython on

**attach_kernel_driver** *(interface: int) → None*

Allow CircuitPython to use the interface if it wants to.

**Parameters**
- **interface** *(int)* – the device interface number to allow CircuitPython to use

### usb_cdc – USB CDC Serial streams

The `usb_cdc` module allows access to USB CDC (serial) communications.

On Windows, each `Serial` is visible as a separate COM port. The ports will often be assigned consecutively, `console` first, but this is not always true.

On Linux, the ports are typically `/dev/ttyACM0` and `/dev/ttyACM1`. The `console` port will usually be first.

On MacOS, the ports are typically `/dev/cu.usbmodem<something>`. The something varies based on the USB bus and port used. The `console` port will usually be first.

#### `usb_cdc.console` : Optional[Serial]

The `console Serial` object is used for the REPL, and for `sys.stdin` and `sys.stdout`. `console` is None if disabled.

However, note that `sys.stdin` and `sys.stdout` are text-based streams, and the `console` object is a binary stream. You do not normally need to write to `console` unless you want to write binary data.

#### `usb_cdc.data` : Optional[Serial]

A `Serial` object that can be used to send and receive binary data to and from the host. Note that `data is disabled` by default. `data` is None if disabled.

#### `usb_cdc.disable()` → None

Do not present any USB CDC device to the host. Can be called in `boot.py`, before USB is connected. Equivalent to `usb_cdc.enable(console=False, data=False)`.

#### `usb_cdc.enable(*, console: bool = True, data: bool = False) → None`

Enable or disable each CDC device. Can be called in `boot.py`, before USB is connected.

**Parameters**
- **bool (data)** – Enable or disable the `console` USB serial device. True to enable; False to disable. Enabled by default.
- **bool** – Enable or disable the `data` USB serial device. True to enable; False to disable. **Disabled** by default.

If you enable too many devices at once, you will run out of USB endpoints. The number of available endpoints varies by microcontroller. CircuitPython will go into safe mode after running `boot.py` to inform you if not enough endpoints are available.

#### `class usb_cdc.Serial`

Receives cdc commands over USB

You cannot create an instance of `usb_cdc.Serial`. The available instances are in the `usb_cdc.serials` tuple.
connected :bool

True if this Serial is connected to a host. (read-only)

Note: The host is considered to be connected if it is asserting DTR (Data Terminal Ready). Most terminal programs and pyserial assert DTR when opening a serial connection. However, the C# SerialPort API does not. You must set SerialPort.DtrEnable.

in_waiting :int

Returns the number of bytes waiting to be read on the USB serial input. (read-only)

out_waiting :int

Returns the number of bytes waiting to be written on the USB serial output. (read-only)

timeout :Optional[float]

The initial value of timeout is None. If None, wait indefinitely to satisfy the conditions of a read operation. If 0, do not wait. If > 0, wait only timeout seconds.

write_timeout :Optional[float]

The initial value of write_timeout is None. If None, wait indefinitely to finish writing all the bytes passed to write(). If 0, do not wait. If > 0, wait only write_timeout seconds.

read(size: int = 1) → bytes

Read at most size bytes. If size exceeds the internal buffer size only the bytes in the buffer will be read. If timeout is > 0 or None, and fewer than size bytes are available, keep waiting until the timeout expires or size bytes are available.

Returns

Data read

Return type

bytes

readinto(buf: circuitpython_typing.WriteableBuffer) → int

Read bytes into the buf. Read at most len(buf) bytes. If timeout is > 0 or None, keep waiting until the timeout expires or len(buf) bytes are available.

Returns

number of bytes read and stored into buf

Return type

int

readline(size: int = -1) → Optional[bytes]

Read a line ending in a newline character ("\n"), including the newline. Return everything readable if no newline is found and timeout is 0. Return None in case of error.

This is a binary stream: the newline character “\n” cannot be changed. If the host computer transmits “\r” it will also be included as part of the line.

Parameters

size (int) – maximum number of characters to read. -1 means as many as possible.

Returns

the line read

Return type

bytes or None
readlines() → List[Optional[bytes]]

Read multiple lines as a list, using readline().

**Warning:** If timeout is None, readlines() will never return, because there is no way to indicate end of stream.

Returns

a list of the line read

Return type

list

write(buf: circuitpython_typing.ReadableBuffer) → int

Write as many bytes as possible from the buffer of bytes.

Returns

the number of bytes written

Return type

int

flush() → None

Force out any unwritten bytes, waiting until they are written.

reset_input_buffer() → None

Clears any unread bytes.

reset_output_buffer() → None

Clears any unwritten bytes.

usb_hid – USB Human Interface Device

The `usb_hid` module allows you to output data as a HID device.

`usb_hid.devices : Tuple[Device, Ellipsis]`

Tuple of all active HID device interfaces. The default set of devices is `Device.KEYBOARD`, `Device.MOUSE`, `Device.CONSUMER_CONTROL`, On boards where `usb_hid` is disabled by default, `devices` is an empty tuple.

If a boot device is enabled by `usb_hid.enable()`, and the host has requested a boot device, the `devices` tuple is replaced when `code.py` starts with a single-element tuple containing a `Device` that describes the boot device chosen (keyboard or mouse). The request for a boot device overrides any other HID devices.

`usb_hid.disable() → None`

Do not present any USB HID devices to the host computer. Can be called in `boot.py`, before USB is connected. The HID composite device is normally enabled by default, but on some boards with limited endpoints, including STM32F4, it is disabled by default. You must turn off another USB device such as `usb_cdc` or `storage` to free up endpoints for use by `usb_hid`.

`usb_hid.enable(devices: Optional[Sequence[Device]], boot_device: int = 0) → None`

Specify which USB HID devices that will be available. Can be called in `boot.py`, before USB is connected.

**Parameters**

- `devices (Sequence)` – `Device` objects. If `devices` is empty, HID is disabled. The order of the `Devices` may matter to the host. For instance, for MacOS, put the mouse device before any Gamepad or Digitizer HID device or else it will not work.
• **boot_device** *(int)* – If non-zero, inform the host that support for a boot HID device is available. If `boot_device=1`, a boot keyboard is available. If `boot_device=2`, a boot mouse is available. No other values are allowed. See below.

If you enable too many devices at once, you will run out of USB endpoints. The number of available endpoints varies by microcontroller. CircuitPython will go into safe mode after running `boot.py` to inform you if not enough endpoints are available.

**Boot Devices**

Boot devices implement a fixed, predefined report descriptor, defined in https://www.usb.org/sites/default/files/hid1_12.pdf, Appendix B. A USB host can request to use the boot device if the USB device says it is available. Usually only a BIOS or other kind of limited-functionality host needs boot keyboard support.

For example, to make a boot keyboard available, you can use this code:

```python
usb_hid.enable((Device.KEYBOARD), boot_device=1)  # 1 for a keyboard
```

If the host requests the boot keyboard, the report descriptor provided by `Device.KEYBOARD` will be ignored, and the predefined report descriptor will be used. But if the host does not request the boot keyboard, the descriptor provided by `Device.KEYBOARD` will be used.

The HID boot device must usually be the first or only device presented by CircuitPython. The HID device will be USB interface number 0. To make sure it is the first device, disable other USB devices, including CDC and MSC (CIRCUITPY). If you specify a non-zero `boot_device`, and it is not the first device, CircuitPython will enter safe mode to report this error.

```python
usb_hid.get_boot_device() → int
```

**Returns**

the boot device requested by the host, if any. Returns 0 if the host did not request a boot device, or if `usb_hid.enable()` was called with `boot_device=0`, the default, which disables boot device support. If the host did request a boot device, returns the value of `boot_device` set in `usb_hid.enable()`: 1 for a boot keyboard, or 2 for boot mouse. However, the standard devices provided by CircuitPython, `Device.KEYBOARD` and `Device.MOUSE`, describe reports that match the boot device reports, so you don’t need to check this if you are using those devices.

**Rtype** int


HID Device specification

Create a description of a USB HID device. The actual device is created when you pass a `Device` to `usb_hid.enable()`.

**Parameters**

• **report_descriptor** *(ReadableBuffer)* – The USB HID Report descriptor bytes. The descriptor is not verified for correctness; it is up to you to make sure it is not malformed.

• **usage_page** *(int)* – The Usage Page value from the descriptor. Must match what is in the descriptor.

• **usage** *(int)* – The Usage value from the descriptor. Must match what is in the descriptor.

• **report_ids** *(Sequence[int])* – Sequence of report ids used by the descriptor. If the `report_descriptor` does not specify any report IDs, use `(0,)`.
• **in_report_lengths** (*Sequence*[int]) – Sequence of sizes in bytes of the HID reports sent to the host. The sizes are in order of the report_ids. Use a size of 0 for a report that is not an IN report. “IN” is with respect to the host.

• **out_report_lengths** (int) – Sequence of sizes in bytes of the HID reports received from the host. The sizes are in order of the report_ids. Use a size of 0 for a report that is not an OUT report. “OUT” is with respect to the host.

`report_ids`, `in_report_lengths`, and `out_report_lengths` must all have the same number of elements.

Here is an example of a `Device` with a descriptor that specifies two report IDs, 3 and 4. Report ID 3 sends an IN report of length 5, and receives an OUT report of length 6. Report ID 4 sends an IN report of length 2, and does not receive an OUT report:

```
device = usb_hid.Device(
    descriptor=b"...", # Omitted for brevity.
    report_ids=(3, 4),
    in_report_lengths=(5, 2),
    out_report_lengths=(6, 0),
)
```

**KEYBOARD :Device**

Standard keyboard device supporting keycodes 0x00-0xDD, modifiers 0xE-0xE7, and five LED indicators. Uses Report ID 1 for its IN and OUT reports.

**MOUSE :Device**

Standard mouse device supporting five mouse buttons, X and Y relative movements from -127 to 127 in each report, and a relative mouse wheel change from -127 to 127 in each report. Uses Report ID 2 for its IN report.

**CONSUMER_CONTROL :Device**

Consumer Control device supporting sent values from 1-652, with no rollover. Uses Report ID 3 for its IN report.

**usage_page :int**

The device usage page identifier, which designates a category of device. (read-only)

**usage :int**

The device usage identifier, which designates a specific kind of device. (read-only)

For example, Keyboard is 0x06 within the generic desktop usage page 0x01. Mouse is 0x02 within the same usage page.


Send an HID report. If the device descriptor specifies zero or one report id’s, you can supply `None` (the default) as the value of `report_id`. Otherwise you must specify which report id to use when sending the report.

**get_last_received_report**(report_id: `Optional[int] = None`) → `Optional[bytes]`

Get the last received HID OUT or feature report for the given report ID. The report ID may be omitted if there is no report ID, or only one report ID. Return `None` if nothing received. After returning a report, subsequent calls will return `None` until next report is received.
usb_host – USB Host

The `usb_host` module allows you to manage USB host ports. To communicate with devices use the `usb` module that is a subset of PyUSB’s API.

```python
class usb_host.Port(dp: microcontroller.Pin, dm: microcontroller.Pin)
    USB host port. Also known as a root hub port.
    Create a USB host port on the given pins. Access attached devices through the `usb` module. Keep this object referenced while interacting with devices, otherwise they will be disconnected.
    
    Parameters
    • `dp` (Pin) – The data plus pin
    • `dm` (Pin) – The data minus pin

definit() → None
    Turn off the USB host port and release the pins for other use.

    __enter__ → Port
    No-op used by Context Managers.

    __exit__ → None
    Automatically deinitializes the hardware when exiting a context. See `Lifetime and ContextManagers` for more info.
```

usb_midi – MIDI over USB

The `usb_midi` module contains classes to transmit and receive MIDI messages over USB.

```python
usb_midi.ports : Tuple[Union[PortIn, PortOut], Ellipsis]
    Tuple of all MIDI ports. Each item is ether `PortIn` or `PortOut`.

usb_midi.disable() → None
    Disable presenting a USB MIDI device to the host. The device is normally enabled by default, but on some boards with limited endpoints including ESP32-S2 and certain STM boards, it is disabled by default. Can be called in boot.py, before USB is connected.

usb_midi.enable() → None
    Enable presenting a USB MIDI device to the host. The device is enabled by default, so you do not normally need to call this function. Can be called in boot.py, before USB is connected.

    If you enable too many devices at once, you will run out of USB endpoints. The number of available endpoints varies by microcontroller. CircuitPython will go into safe mode after running boot.py to inform you if not enough endpoints are available.

class usb_midi.PortIn
    Receives midi commands over USB

    You cannot create an instance of `usb_midi.PortIn`.

    PortIn objects are constructed for every corresponding entry in the USB descriptor and added to the `usb_midi.ports` tuple.

    read(nbytes: Optional[int] = None) → Optional[bytes]
        Read characters. If `nbytes` is specified then read at most that many bytes. Otherwise, read everything that arrives until the connection times out. Providing the number of bytes expected is highly recommended because it will be faster.
```
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**Returns**
- Data read

**Return type**
- bytes or None

`readinto(buf: circuitpython_typing.WriteableBuffer, nbytes: Optional[int] = None) → Optional[bytes]`

Read bytes into the `buf`. If `nbytes` is specified then read at most that many bytes. Otherwise, read at most `len(buf)` bytes.

**Returns**
- number of bytes read and stored into `buf`

**Return type**
- bytes or None

**class usb_midi.PortOut**

Sends midi messages to a computer over USB

You cannot create an instance of `usb_midi.PortOut`.

PortOut objects are constructed for every corresponding entry in the USB descriptor and added to the `usb_midi.ports` tuple.

`write(buf: circuitpython_typing.ReadableBuffer) → Optional[int]`

Write the buffer of bytes to the bus.

**Returns**
- the number of bytes written

**Return type**
- int or None

**ustack – Stack information and analysis**

`ustack.max_stack_usage() → int`

Return the maximum excursion of the stack so far.

`ustack.stack_size() → int`

Return the size of the entire stack. Same as in `micropython.mem_info()`, but returns a value instead of just printing it.

`ustack.stack_usage() → int`

Return how much stack is currently in use. Same as `micropython.stack_use()`; duplicated here for convenience.

**vectorio – Lightweight 2D shapes for displays**

The `vectorio` module provide simple filled drawing primitives for use with `displayio`.

```python
group = displayio.Group()
palette = displayio.Palette(1)
palette[0] = 0x125690
circle = vectorio.Circle(pixel_shader=palette, radius=25, x=70, y=40)
group.append(circle)
```

(continues on next page)
rectangle = vectorio.Rectangle(pixel_shader=palette, width=40, height=30, x=55, y=45)
group.append(rectangle)

points=[(5, 5), (100, 20), (20, 20), (20, 100)]
polygon = vectorio.Polygon(pixel_shader=palette, points=points, x=0, y=0)
group.append(polygon)

class vectorio.Circle(pixel_shader: Union[displayio.ColorConverter, displayio.Palette], radius: int, x: int, y: int)

Circle is positioned on screen by its center point.

Parameters

• **pixel_shader** *(Union[ColorConverter, Palette])* – The pixel shader that produces colors from values

• **radius** *(int)* – The radius of the circle in pixels

• **x** *(int)* – Initial x position of the axis.

• **y** *(int)* – Initial y position of the axis.

• **color_index** *(int)* – Initial color_index to use when selecting color from the palette.

radius :int

The radius of the circle in pixels.

color_index :int

The color_index of the circle as 0 based index of the palette.

x :int

X position of the center point of the circle in the parent.

y :int

Y position of the center point of the circle in the parent.

hidden :bool

Hide the circle or not.

location :Tuple[int, int]

(X,Y) position of the center point of the circle in the parent.

pixel_shader :Union[displayio.ColorConverter, displayio.Palette]

The pixel shader of the circle.

class vectorio.Polygon(pixel_shader: Union[displayio.ColorConverter, displayio.Palette], points: List[Tuple[int, int]], x: int, y: int)

Represents a closed shape by ordered vertices. The path will be treated as ‘closed’, the last point will connect to the first point.

Parameters

• **pixel_shader** *(Union[ColorConverter, Palette])* – The pixel shader that produces colors from values

• **points** *(List[Tuple[int, int]])* – Vertices for the polygon

• **x** *(int)* – Initial screen x position of the 0,0 origin in the points list.
• y (int) – Initial screen y position of the 0,0 origin in the points list.
• color_index (int) – Initial color_index to use when selecting color from the palette.

points :List[Tuple[int, int]]
Vertices for the polygon.

color_index :int
The color_index of the polygon as 0 based index of the palette.

x :int
X position of the 0,0 origin in the points list.
y :int
Y position of the 0,0 origin in the points list.

hidden :bool
Hide the polygon or not.

location :Tuple[int, int]
(X,Y) position of the 0,0 origin in the points list.

pixel_shader :Union[displayio.ColorConverter, displayio.Palette]
The pixel shader of the polygon.

class vectorio.Rectangle(pixel_shader: Union[displayio.ColorConverter, displayio.Palette], width: int, height: int, x: int, y: int)
Represents a rectangle by defining its bounds

Parameters

• pixel_shader (Union[ColorConverter, Palette]) – The pixel shader that produces colors from values
• width (int) – The number of pixels wide
• height (int) – The number of pixels high
• x (int) – Initial x position of the top left corner.
• y (int) – Initial y position of the top left corner.
• color_index (int) – Initial color_index to use when selecting color from the palette.

width :int
The width of the rectangle in pixels.

height :int
The height of the rectangle in pixels.

color_index :int
The color_index of the rectangle in 1 based index of the palette.

x :int
X position of the top left corner of the rectangle in the parent.
y :int
Y position of the top left corner of the rectangle in the parent.

hidden :bool
Hide the rectangle or not.
location : Tuple[int, int]
    (X,Y) position of the top left corner of the rectangle in the parent.

pixel_shader : Union[displayio.ColorConverter, displayio.Palette]
    The pixel shader of the rectangle.

**watchdog – Watchdog Timer**

The `watchdog` module provides support for a Watchdog Timer. This timer will reset the device if it hasn’t been fed after a specified amount of time. This is useful to ensure the board has not crashed or locked up. Note that on some platforms the watchdog timer cannot be disabled once it has been enabled.

The `WatchDogTimer` is used to restart the system when the application crashes and ends up into a non recoverable state. Once started it cannot be stopped or reconfigured in any way. After enabling, the application must “feed” the watchdog periodically to prevent it from expiring and resetting the system.

Example usage:

```python
from microcontroller import watchdog as w
from watchdog import WatchDogMode
w.timeout = 2.5  # Set a timeout of 2.5 seconds
w.mode = WatchDogMode.RAISE
w.feed()
```

**exception watchdog.WatchDogTimeout**

Bases: Exception

Exception raised when the watchdog timer is set to `WatchDogMode.RAISE` and expires.

Example:

```python
import microcontroller
import watchdog
import time

wdt = microcontroller.watchdog
wdt.timeout = 5

while True:
    wdt.mode = watchdog.WatchDogMode.RAISE
    print("Starting loop -- should exit after five seconds")
    try:
        while True:
            time.sleep(10)  # Also works with pass
        except watchdog.WatchDogTimeout as e:
            print("Watchdog expired")
        except Exception as e:
            print("Other exception")

    print("Exited loop")
```

Initialize self. See help(type(self)) for accurate signature.

**class watchdog.WatchDogMode**

run state of the watchdog timer
Enum-like class to define the run mode of the watchdog timer.

**RAISE :**WatchDogMode

Raise an exception when the WatchDogTimer expires.

**Limitations:** RAISE mode is not supported on SAMD or RP2040.

**RESET :**WatchDogMode

Reset the system if the WatchDogTimer expires.

class watchdog.WatchDogTimer

Timer that is used to detect code lock ups and automatically reset the microcontroller when one is detected.

A lock up is detected when the watchdog hasn’t been fed after a given duration. So, make sure to call `feed` within the timeout.

Not currently dynamically supported. Access the sole instance through `microcontroller.watchdog`.

**timeout :**float

The maximum number of seconds that can elapse between calls to `feed()`

**mode :**WatchDogMode

The current operating mode of the WatchDogTimer `watchdog.WatchDogMode`.

Setting a WatchDogMode activates the WatchDog:

```python
import microcontroller
import watchdog

w = microcontroller.watchdog
w.timeout = 5
w.mode = watchdog.WatchDogMode.RAISE
```

Once set, the WatchDogTimer will perform the specified action if the timer expires.

**feed() → None**

Feed the watchdog timer. This must be called regularly, otherwise the timer will expire.

**deinit() → None**

Stop the watchdog timer. This may raise an error if the watchdog timer cannot be disabled on this platform.

**wifi**

The `wifi` module provides necessary low-level functionality for managing wifi connections. Use `socketpool` for communicating over the network.

**wifi.radio :**Radio

Wifi radio used to manage both station and AP modes. This object is the sole instance of `wifi.Radio`.

**class wifi.AuthMode**

The authentication protocols used by WiFi.

**OPEN :**object

Open network. No authentication required.
WEP :object
Wired Equivalent Privacy.

WPA :object
Wireless Protected Access.

WPA2 :object
Wireless Protected Access 2.

WPA3 :object
Wireless Protected Access 3.

PSK :object
Pre-shared Key. (password)

ENTERPRISE :object
Each user has a unique credential.

class wifi.Monitor
For monitoring WiFi packets.

wifi.__init__(self, channel: Optional[int] = 1, queue: Optional[int] = 128) → None
Initialize wifi.Monitor singleton.

Parameters
- channel (int) – The WiFi channel to scan.
- queue (int) – The queue size for buffering the packet.

wifi.channel :int
The WiFi channel to scan.

wifi.queue :int
The queue size for buffering the packet.

wifi.deinit(self) → None
De-initialize wifi.Monitor singleton.

wifi.lost(self) → int
Returns the packet loss count. The counter resets after each poll.

wifiqueued(self) → int
Returns the packet queued count.

wifi.packet(self) → dict
Returns the monitor packet.

class wifi.Network
A wifi network provided by a nearby access point.

You cannot create an instance of wifi.Network. They are returned by wifi.Radio.

start_scanning_networks.

ssid :str
String id of the network

bssid :bytes
BSSID of the network (usually the AP’s MAC address)
**rssi : int**
Signal strength of the network

**channel : int**
Channel number the network is operating on

**country : str**
String id of the country code

**authmode : str**
String id of the authmode

class wifi.Packet
The packet parameters.

**CH : object**
The packet’s channel.

**LEN : object**
The packet’s length.

**RAW : object**
The packet’s payload.

**RSSI : object**
The packet’s rssi.

class wifi.Radio
Native wifi radio.
This class manages the station and access point functionality of the native Wifi radio.
You cannot create an instance of wifi.Radio. Use wifi.radio to access the sole instance available.

**enabled : bool**
True when the wifi radio is enabled. If you set the value to False, any open sockets will be closed.

**hostname : Union[str | ReadableBuffer]**
Hostname for wifi interface. When the hostname is altered after interface started/connected the changes would only be reflected once the interface restarts/reconnects.

**mac_address : circuitpython_typing.ReadableBuffer**
MAC address for the station. When the address is altered after interface is connected the changes would only be reflected once the interface reconnects.

**tx_power : float**
Wifi transmission power, in dBm.

**mac_address_ap : circuitpython_typing.ReadableBuffer**
MAC address for the AP. When the address is altered after interface is started the changes would only be reflected once the interface restarts.

**ipv4_gateway : Optional[ipaddress.IPv4Address]**
IP v4 Address of the station gateway when connected to an access point. None otherwise.

**ipv4_gateway_ap : Optional[ipaddress.IPv4Address]**
IP v4 Address of the access point gateway, when enabled. None otherwise.
ipv4_subnet :Optional[ipaddress.IPv4Address]
    IP v4 Address of the station subnet when connected to an access point. None otherwise.

ipv4_subnet_ap :Optional[ipaddress.IPv4Address]
    IP v4 Address of the access point subnet, when enabled. None otherwise.

ipv4_address :Optional[ipaddress.IPv4Address]
    IP v4 Address of the station when connected to an access point. None otherwise.

ipv4_address_ap :Optional[ipaddress.IPv4Address]
    IP v4 Address of the access point, when enabled. None otherwise.

ipv4_dns :ipaddress.IPv4Address
    IP v4 Address of the DNS server to be used.

ap_info :Optional[Network]
    Network object containing BSSID, SSID, authmode, channel, country and RSSI when connected to an
    access point. None otherwise.

start_scanning_networks(*, start_channel: int = 1, stop_channel: int = 11) → Iterable[Network]
    Scans for available wifi networks over the given channel range. Make sure the channels are allowed in your
    country.

    Note: In the raspberrypi port (RP2040 CYW43), start_channel and stop_channel are ignored.

stop_scanning_networks() → None
    Stop scanning for Wifi networks and free any resources used to do it.

start_station() → None
    Starts a Station.

stop_station() → None
    Stops the Station.

start_ap(ssid: Union[str | ReadableBuffer], password: Union[str | ReadableBuffer] = b'', *, channel: int = 1, authmode: Optional[AuthMode] = None, max_connections: Optional[int] = 4) → None
    Starts an Access Point with the specified ssid and password.
    If channel is given, the access point will use that channel unless a station is already operating on a different
    channel.
    If authmode is not None, the access point will use that Authentication mode. If a non-empty password
    is given, authmode must not be OPEN. If authmode is not given or is None, OPEN will be used when the
    password is the empty string, otherwise authmode will be WPA_WPA2_PSK.
    If max_connections is given, the access point will allow up to that number of stations to connect.

stop_ap() → None
    Stops the Access Point.

cnect(ssid: Union[str | ReadableBuffer], password: Union[str | ReadableBuffer] = b'', *, channel: int = 0, 
    bssid: Optional[Union[str | ReadableBuffer]] = None, timeout: Optional[float] = None) → None
    Connects to the given ssid and waits for an ip address. Reconnections are handled automatically once one
    connection succeeds.
    By default, this will scan all channels and connect to the access point (AP) with the given ssid and greatest
    signal strength (rssi).
If channel is non-zero, the scan will begin with the given channel and connect to the first AP with the given ssid. This can speed up the connection time significantly because a full scan doesn’t occur.

If bssid is given and not None, the scan will start at the first channel or the one given and connect to the AP with the given bssid and ssid.

```python
def set_ipv4_address(*, ipv4: ipaddress.IPv4Address, netmask: ipaddress.IPv4Address, gateway: ipaddress.IPv4Address, ipv4_dns: Optional[ipaddress.IPv4Address]) -> None
```

Sets the IP v4 address of the station. Must include the netmask and gateway. DNS address is optional. Setting the address manually will stop the DHCP client.

```python
def start_dhcp() -> None
    # Starts the DHCP client.
```

```python
def stop_dhcp() -> None
    # Stops the DHCP client. Needed to assign a static IP address.
```

```python
def ping(ip: ipaddress.IPv4Address, *, timeout: Optional[float] = 0.5) -> Optional[float]
```

Ping an IP to test connectivity. Returns echo time in seconds. Returns None when it times out.

```python
class wifi.ScannedNetworks
```

Iterates over all `wifi.Network` objects found while scanning. This object is always created by a `wifi.Radio`: it has no user-visible constructor.

Cannot be instantiated directly. Use `wifi.Radio.start_scanning_networks`.

```python
__iter__() -> Iterator[Network]
```

Returns itself since it is the iterator.

```python
__next__() -> Network
```

Returns the next `wifi.Network`. Raises `StopIteration` if scanning is finished and no other results are available.

**zlib – zlib decompression functionality**

The `zlib` module allows limited functionality similar to the CPython zlib library. This module allows to decompress binary data compressed with DEFLATE algorithm (commonly used in zlib library and gzip archiver). Compression is not yet implemented.

```python
zlib.zlib_decompress(data: bytes, wbits: Optional[int] = 0, bufsize: Optional[int] = 0) -> bytes
```

Return decompressed `data` as bytes. `wbits` is DEFLATE dictionary window size used during compression (8-15, the dictionary size is power of 2 of that value). Additionally, if value is positive, `data` is assumed to be zlib stream (with zlib header). Otherwise, if it’s negative, it’s assumed to be raw DEFLATE stream.

The `wbits` parameter controls the size of the history buffer (or “window size”), and what header and trailer format is expected.

Common `wbits` values:

- To decompress deflate format, use `wbits = -15`
- To decompress zlib format, use `wbits = 15`
- To decompress gzip format, use `wbits = 31`

**Parameters**

- `data (bytes)` – data to be decompressed
- `wbits (int)` – DEFLATE dictionary window size used during compression. See above.
• **bufsize** *(int)* – ignored for compatibility with CPython only

**help() – Built-in method to provide helpful information**

```python
help(object=None)
```

Prints a help method about the given object. When `object` is none, prints general port information.

### 1.8.2 Supported Ports

CircuitPython supports a number of microcontroller families. Support quality for each varies depending on the active contributors for each port.

Adafruit sponsored developers are actively contributing to atmel-samd, mimxrt10xx, nrf and stm ports. They also maintain the other ports in order to ensure the boards build. Additional testing is limited.

**SAMD21 and SAMD51**

This port supports many development boards that utilize SAMD21 and SAMD51 chips. See [https://circuitpython.org/downloads](https://circuitpython.org/downloads) for all supported boards.

**Building**

For build instructions see this guide: [https://learn.adafruit.com/building-circuitpython/](https://learn.adafruit.com/building-circuitpython/)

**Debugging**

For debugging instructions see this guide: [https://learn.adafruit.com/debugging-the-samd21-with-gdb](https://learn.adafruit.com/debugging-the-samd21-with-gdb)

**Port Specific modules**

**CircuitPython port to Spresense**

This directory contains the port of CircuitPython to Spresense. It is a compact development board based on Sony’s power-efficient multicore microcontroller CXD5602.

Board features:

• Integrated GPS
  - The embedded GNSS with support for GPS, QZSS and GLONASS enables applications where tracking is required.

• Hi-res audio output and multi mic inputs
  - Advanced 192kHz/24 bit audio codec and amplifier for audio output, and support for up to 8 mic input channels.

• Multicore microcontroller
  - Spresense is powered by Sony’s CXD5602 microcontroller (ARM® Cortex®-M4F × 6 cores), with a clock speed of 156 MHz.
Currently, Spresense port does not support Audio and Multicore.
Refer to developer.sony.com/develop/spresense/ for further information about this board.

Prerequisites

Linux

Add user to dialout group:

```
$ sudo usermod -a -G dialout <user-name>
```

Windows

Download and install USB serial driver

- CP210x USB to serial driver for Windows 7/8/8.1
- CP210x USB to serial driver for Windows 10

macOS

Download and install USB serial driver

- CP210x USB to serial driver for Mac OS X

Build instructions

Pull all submodules into your clone:

```
$ git submodule update --init --recursive
```

Build the MicroPython cross-compiler:

```
$ make -C mpy-cross
```

Change directory to cxd56:

```
$ cd ports/cxd56
```

To build circuitpython image run:

```
$ make BOARD=spresense
```
USB connection

Connect the Spresense main board to the PC via the USB cable.

Flash the bootloader

The correct bootloader is required for the Spresense board to function.

Bootloader information:

- The bootloader has to be flashed the very first time the board is used.
- You have to accept the End User License Agreement to be able to download and use the Spresense bootloader binary.

Download the spresense binaries zip archive from: Spresense firmware v2-3-000

Extract spresense binaries in your PC to ports/spresense/spresense-exported-sdk/firmware/

To flash the bootloader run the command:

```
$ make BOARD=spresense flash-bootloader
```

Flash the circuitpython image

To flash the firmware run the command:

```
$ make BOARD=spresense flash
```

Accessing the board

Connect the Spresense extension board to the PC via the USB cable.

Once built and deployed, access the CircuitPython REPL (the Python prompt) via USB. You can run:

```
$ screen /dev/ttyACM0 115200
```

CircuitPython on Espressif SoCs

This port adds the Espressif line of SoCs to CircuitPython.

Support Status:

<table>
<thead>
<tr>
<th>SoC</th>
<th>Status</th>
</tr>
</thead>
<tbody>
<tr>
<td>ESP</td>
<td>beta</td>
</tr>
<tr>
<td>ESP32-C3</td>
<td>beta</td>
</tr>
<tr>
<td>ESP32-S2</td>
<td>stable</td>
</tr>
<tr>
<td>ESP32-S3</td>
<td>beta</td>
</tr>
</tbody>
</table>
How this port is organized:

- **bindings/** contains some required bindings to the ESP-IDF for exceptions and memory.
- **boards/** contains the configuration files for each development board and breakout available on the port.
- **common-hal/** contains the port-specific module implementations, used by shared-module and shared-bindings.
- **esp-idf/** contains the Espressif IoT Development Framework installation, including all the drivers for the port.
- **peripherals/** contains peripheral setup files and peripheral mapping information, sorted by family and sub-variant. Most files in this directory can be generated with the python scripts in **tools/**.
- **supervisor/** contains port-specific implementations of internal flash, serial and USB, as well as the port.c file, which initializes the port at startup.
- **tools/** includes useful Python scripts for debugging and other purposes.

At the root level, refer to **mpconfigboard.h** and **mpconfigport.mk** for port specific settings and a list of enabled CircuitPython modules.

Connecting to the ESP32

The ESP32 chip itself has no USB support. On many boards there is a USB-serial adapter chip, such as a CP2102N, CP2104 or CH9102F, usually connected to the ESP32 TXD0 (GPIO1) and RXD0 (GPIO3) pins, for access to the bootloader. CircuitPython also uses this serial channel for the REPL.

Connecting to the ESP32-C3

USB Connection:

On ESP32-C3 REV3 chips, a USB Serial/JTAG Controller is available. Note: This USB connection cannot be used for a CIRCUITPY drive.

Depending on the board you have, the USB port may or may not be connected to native USB.

The following connections need to be made if native USB isn’t available on the USB port:

<table>
<thead>
<tr>
<th>GPIO</th>
<th>USB</th>
</tr>
</thead>
<tbody>
<tr>
<td>19</td>
<td>D+ (green)</td>
</tr>
<tr>
<td>18</td>
<td>D- (white)</td>
</tr>
<tr>
<td>GND</td>
<td>GND (black)</td>
</tr>
<tr>
<td>5V</td>
<td>5V (red)</td>
</tr>
</tbody>
</table>

Connect these pins using a USB adapter or breakout cable.

UART Connection:

A USB to UART convertor can be used for connecting to ESP32-C3 to get access to the serial console and REPL and for flashing CircuitPython.

The following connections need to be made in this case:
BLE Connection:
This feature is not yet available and currently under development.

Connecting to the ESP32-S2

USB Connection:
Depending on the board you have, the USB port may or may not be connected to native USB.
The following connections need to be made if native USB isn’t available on the USB port:

<table>
<thead>
<tr>
<th>GPIO</th>
<th>USB</th>
</tr>
</thead>
<tbody>
<tr>
<td>20</td>
<td>D+ (green)</td>
</tr>
<tr>
<td>19</td>
<td>D- (white)</td>
</tr>
<tr>
<td>GND</td>
<td>GND (black)</td>
</tr>
<tr>
<td>5V</td>
<td>5V (red)</td>
</tr>
</tbody>
</table>

Connect these pins using a USB adapter or breakout cable to access the CircuitPython drive.

UART Connection:
A USB to UART convertor can be used for connecting to ESP32-S2 to get access to the serial console and REPL and for flashing CircuitPython.
The following connections need to be made in this case:

<table>
<thead>
<tr>
<th>GPIO</th>
<th>UART</th>
</tr>
</thead>
<tbody>
<tr>
<td>43</td>
<td>RX</td>
</tr>
<tr>
<td>44</td>
<td>TX</td>
</tr>
<tr>
<td>GND</td>
<td>GND</td>
</tr>
<tr>
<td>5V</td>
<td>5V</td>
</tr>
</tbody>
</table>

BLE Connection:
This feature isn’t available on ESP32-S2.

Connecting to the ESP32-S3

USB Connection:
Depending on the board you have, the USB port may or may not be connected to native USB.
The following connections need to be made if native USB isn’t available on the USB port:
GPIO | USB
---|---
20 | D+ (green)
19 | D- (white)
GND | GND (black)
5V | 5V (red)

Connect these pins using a USB adapter or breakout cable to access the CircuitPython drive.

UART Connection:

A USB to UART convertor can be used for connecting to ESP32-S3 to get access to the serial console and REPL and for flashing CircuitPython.

The following connections need to be made in this case:

| GPIO | UART |
---|---|
43 | RX |
44 | TX |
GND | GND |
5V | 5V |

BLE Connection:

This feature is not yet available and currently under development.

Building and flashing

Before building or flashing the, you must install the ESP-IDF.

Note: This must be re-done every time the ESP-IDF is updated, but not every time you build.

Run `cd ports/espressif from circuitpython/` to move to the espressif port root, and run:

```
./esp-idf/install.sh
```

After this initial installation, you must add the ESP-IDF tools to your path.

Note: This must be re-done every time you open a new shell environment for building or flashing.

Run `cd ports/espressif from circuitpython/` to move to the espressif port root, and run:

```
./esp-idf/export.sh
```

When CircuitPython updates the ESP-IDF to a new release, you may need to run this installation process again. The exact commands used may also vary based on your shell environment.

Building boards is typically done through `make BOARD=board_id`. The default port is `tty.SLAB_USBtoUART`, which will only work on certain Mac setups. On most machines, both Mac and Linux, you will need to set the port yourself by running `ls /dev/tty.usb*` and selecting the one that only appears when your development board is plugged in. An example make command with the port setting is as follows:

```
made BOARD=board_id PORT=/dev/tty.usbserial-1421120 flash
```

`board_id` is the unique board identifier in CircuitPython. It is the same as the name of the board in the `boards` directory.
**Debugging**

TODO: Add documentation for ESP32-C3/S3 JTAG feature.

The ESP32-S2 supports JTAG debugging over OpenOCD using a JLink or other probe hardware. The official tutorials can be found on the Espressif website [here](#), but they are mostly for the ESP32-S2 Kaluga, which has built-in debugging.

OpenOCD is automatically installed and added to your bash environment during the ESP-IDF installation and setup process. You can double check that it is installed by using `openocd --version`, as per the tutorial. Attach the JTAG probe pins according to the instructions for JTAG debugging on boards that do not contain an integrated debugger.

Once the debugger is connected physically, you must run OpenOCD with attached configuration files specifying the **interface** (your debugger probe) and either a **target** or a **board** (targets are for SoCs only, and can be used when a full board configuration file doesn’t exist). You can find the location of these files by checking the `OPENOCD_SCRIPTS` environmental variable by running `echo $OPENOCD_SCRIPTS`. Interfaces will be in the `interface/` directory, and targets and boards in the `target/` and `board/` directories, respectively.

**Note:** Unfortunately, there are no board files for the esp32-s2 other than the Kaluga, and the included target/esp32s2.cfg target file will not work by default on the JLink for boards like the Saola 1, as the default speed is incorrect. In addition, these files are covered under the GPL and cannot be included in CircuitPython. Thus, you must make a copy of the esp32s2.cfg file yourself and add the following line manually, under `transport select jtag` at the start of the file:

```
adapter_khz 1000
```

Once this is complete, your final OpenOCD command may look something like this:

```
openocd -f interface/jlink.cfg -f SOMEPATH/copied-esp32s2-saola-1.cfg
```

Where SOMEPATH is the location of your copied configuration file (this can be placed in the `port/boards` directory with a prefix to ignore it with `.gitignore`, for instance). Interface, target and board config files sourced from Espressif only need their paths from the `OPENOCD_SCRIPTS` location, you don’t need to include their full path. Once OpenOCD is running, connect to GDB with:

```
xtensa-esp32s2-elf-gdb build-espressif_saola_1_wrover/firmware.elf
```

And follow the Espressif GDB tutorial instructions for connecting, or add them to your `gdbinit`:

```
target remote :3333
set remote hardware-watchpoint-limit 2
mon reset halt
flushregs
thb app_main
```

**LiteX (FPGA)**

LiteX is a Python-based System on a Chip (SoC) designer for open source supported Field Programmable Gate Array (FPGA) chips. This means that the CPU core(s) and peripherals are not defined by the physical chip. Instead, they are loaded as separate “gateware”. Once this gateware is loaded, CircuitPython can be loaded on top of it to work as expected.
Installation

You'll need `dfu-util` to install CircuitPython on the Fomu.

Make sure the foboot bootloader is updated. Instructions are here: https://github.com/im-tomu/fomu-workshop/blob/master/docs/bootloader.rst

Once you’ve updated the bootloader, you should know how to use `dfu-util`. It's pretty easy!

To install CircuitPython do:

```
```

It will install and then restart. CIRCUITPY should appear as it usually does and work the same.

CircuitPython Port To The NXP i.MX RT10xx Series

This is a port of CircuitPython to the i.MX RT10xx series of chips.

CircuitPython Port To The Nordic Semiconductor nRF52 Series

This is a port of CircuitPython to the Nordic Semiconductor nRF52 series of chips.

**NOTE**: There are board-specific READMEs that may be more up to date than the generic board-neutral documentation below.

Flash

Some boards have UF2 bootloaders and can simply be flashed in the normal way, by copying `firmware.uf2` to the BOOT drive.

For some boards, you can use the `flash` target:

```
make BOARD=pca10056 flash
```

Segger Targets

Install the necessary tools to flash and debug using Segger:

- JLink Download
- `nrfjprog linux-32bit` Download
- `nrfjprog linux-64bit` Download
- `nrfjprog osx` Download
- `nrfjprog win32` Download

note: On Linux it might be required to link SEGGER’s `libjlinkarm.so` inside `nrfjprog`’s folder.
DFU Targets

run follow command to install adafruit-nrfutil from PyPi

```
$ pip3 install --user adafruit-nrfutil
```

**make flash** and **make sd** will not work with DFU targets. Hence, **dfu-gen** and **dfu-flash** must be used instead.

- dfu-gen: Generates a Firmware zip to be used by the DFU flash application.
- dfu-flash: Triggers the DFU flash application to upload the firmware from the generated Firmware zip file.

When enabled you have different options to test it:

- NUS Console for Linux (recommended)
- WebBluetooth REPL (experimental)

RP2040

This port supports many development boards that utilize RP2040 chips. See https://circuitpython.org/downloads for all supported boards.

Building

For build instructions see this guide: https://learn.adafruit.com/building-circuitpython/

Port Specific modules

Circuitpython on STM32

This port brings the ST Microelectronics STM32 series of MCUs to Circuitpython. STM32 chips have a wide range of capability, from <$1 low power STM32F0s to dual-core STM32H7s running at 400+ MHz. Currently, only the F4, F7, and H7 families are supported, powered by the ARM Cortex M4 and M7 processors.

Refer to the ST Microelectronics website for more information on features sorted by family and individual chip lines: st.com/en/microcontrollers-microprocessors/stm32-high-performance-mcus.html

STM32 SoCs vary product-by-product in clock speed, peripheral capability, pin assignments, and their support within this port. Refer to mpconfigport.mk for a full list of enabled modules sorted by family.

How this port is organized:

- **boards/** contains the configuration files for each development board and breakout available on the port, as well as system files and both shared and SoC-specific linker files. Board configuration includes a pin mapping of the board, oscillator information, board-specific build flags, and setup for OLED or TFT screens where applicable.
- **common-hal/** contains the port-specific module implementations, used by shared-module and shared-bindings.
- **packages/** contains package-specific pin bindings (LQFP100, BGA216, etc)
- **peripherals/** contains peripheral setup files and peripheral mapping information, sorted by family and sub-variant. Most files in this directory can be generated with the python scripts in tools/.
- **st-driver/** submodule for ST HAL and LL files generated via CubeMX. Shared with TinyUSB.
• **supervisor/** contains port-specific implementations of internal flash, serial and USB, as well as the **port.c** file, which initializes the port at startup.

• **tools/** python scripts for generating peripheral and pin mapping files in **peripherals/** and **board/**.

At the root level, refer to **mpconfigboard.h** and **mpconfigport.mk** for port specific settings and a list of enabled modules.

### Build instructions

Ensure your clone of CircuitPython is ready to build by following the [guide on the Adafruit Website](https://www.adafruit.com). This includes installing the toolchain, synchronizing submodules, and running **mpy-cross**.

Once the one-time build tasks are complete, you can build at any time by navigating to the port directory:

```
$ cd ports/stm
```

To build for a specific CircuitPython board, run:

```
$ make BOARD=feather_stm32f405_express
```

You may also build with certain flags available in the makefile, depending on your board and development goals. The following flags would enable debug information and correct flash locations for a pre-flashed UF2 bootloader:

```
$ make BOARD=feather_stm32f405_express DEBUG=1 UF2_BOOTLOADER=1
```

### USB connection

Connect your development board of choice to the host PC via the USB cable. Note that for most ST development boards such as the Nucleo and Discovery series, you must use a secondary OTG USB connector to access CircuitPython, as the primary USB connector will be connected to a built-in ST-Link debugger rather than the chip itself.

In many cases, this ST-Link USB connector will still need to be connected to power for the chip to turn on - refer to your specific product manual for details.

### Flash the bootloader

Most ST development boards come with a built-in STLink programming and debugging probe accessible via USB. This programmer may show up as an **MBED** drive on the host PC, enabling simple drag and drop programming with a .bin file, or they may require a tool like OpenOCD or StLink-org/stlink to run flashing and debugging commands.

Many hobbyist and 3rd party development boards also expose SWD pins. These can be used with a cheap stlink debugger or other common programmers.

For non-ST products or users without a debugger, all STM32 boards in the high performance families (F4, F7 and H7) include a built-in DFU bootloader stored in ROM. This bootloader is accessed by ensuring the BOOT0 pin is held to a logic 1 and the BOOT1 pin is held to a logic 0 when the chip is reset ([ST Appnote AN2606](https://www.st.com). Most chips hold BOOT low by default, so this can usually be achieved by running a jumper wire from 3.3V power to the BOOT0 pin, if it is exposed, or by flipping the appropriate switch or button as the chip is reset. Once the chip is started in DFU mode, BOOT0 no longer needs to be held high and can be released. An example is available in the Feather STM32F405 guide.

Windows users will need to install **stm32cubeprog**, while Mac and Linux users will need to install **dfu-util** with `brew install dfu-util` or `sudo apt-get install dfu-util`. More details are available in the Feather F405 guide.
Flashing the circuitpython image with DFU-Util

Ensure the board is in dfu mode by following the steps in the previous section. Then run:

```
$ make BOARD=feather_stm32F405_express flash
```

Alternatively, you can navigate to the build directory and run the raw dfu-util command:

```
dfu-util -a 0 --dfuse-address 0x08000000 -D firmware.bin
```

Accessing the board

Connecting the board to the PC via the USB cable will allow code to be uploaded to the CIRCUITPY volume.

Circuitpython exposes a CDC virtual serial connection for REPL access and debugging. Connecting to it from OSX will look something like this:

```
screen /dev/tty.usbmodem14111201 115200
```

You may also use a program like mu to assist with REPL access.

1.8.3 Troubleshooting

From time to time, an error occurs when working with CircuitPython. Here are a variety of errors that can happen, what they mean and how to fix them.

File system issues

If your host computer starts complaining that your CIRCUITPY drive is corrupted or files cannot be overwritten or deleted, then you will have to erase it completely. When CircuitPython restarts it will create a fresh empty CIRCUITPY filesystem.

Corruption often happens on Windows when the CIRCUITPY disk is not safely ejected before being reset by the button or being disconnected from USB. This can also happen on Linux and Mac OSX but it’s less likely.

Caution: To erase and re-create CIRCUITPY (for example, to correct a corrupted filesystem), follow one of the procedures below. It’s important to note that any files stored on the CIRCUITPY drive will be erased. Back up your code if possible before continuing!

REPL Erase Method

This is the recommended method of erasing your board. If you are having trouble accessing the CIRCUITPY drive or the REPL, consider first putting your board into safe mode.

To erase any board if you have access to the REPL:

1. Connect to the CircuitPython REPL using a terminal program.
2. Type `import storage` into the REPL.
3. Then, type `storage.erase_filesystem()` into the REPL.
4. The CIRCUITPY drive will be erased and the board will restart with an empty CIRCUITPY drive.
Erase File Method

If you do not have access to the REPL, you may still have options to erase your board.

The Erase CIRCUITPY Without Access to the REPL section of the Troubleshooting page in the Welcome to Circuit-Python guide covers the non-REPL erase process for various boards. Visit the guide, find the process that applies to your board, and follow the instructions to erase your board.

ValueError: Incompatible .mpy file.

This error occurs when importing a module that is stored as a mpy binary file (rather than a py text file) that was generated by a different version of CircuitPython than the one it’s being loaded into. Most versions are compatible but, rarely they aren’t. In particular, the mpy binary format changed between CircuitPython versions 1.x and 2.x, 2.x and 3.x, and will change again between 6.x and 7.x.

So, for instance, if you just upgraded to CircuitPython 7.x from 6.x you’ll need to download a newer version of the library that triggered the error on import. They are all available in the Adafruit bundle and the Community bundle. Make sure to download a version with 7.0.0 or higher in the filename.

1.8.4 Additional CircuitPython Libraries and Drivers on GitHub

These are libraries and drivers available in separate GitHub repos. They are designed for use with CircuitPython and may or may not work with MicroPython.

Adafruit CircuitPython Library Bundle

We provide a bundle of all our libraries to ease installation of drivers and their dependencies. The bundle is primarily geared to the Adafruit Express line of boards which feature a relatively large external flash. With Express boards, it’s easy to copy them all onto the filesystem. However, if you don’t have enough space simply copy things over as they are needed.

- The Adafruit bundles are available on GitHub: <https://github.com/adafruit/Adafruit_CircuitPython_Bundle/releases>.
- Documentation for the bundle, which includes links to documentation for all libraries, is available here: <https://circuitpython.readthedocs.io/projects/bundle/en/latest/>.

CircuitPython Community Library Bundle

This bundle contains non-Adafruit sponsored libraries, that are written and submitted by members of the community.

- The Community bundles are available on GitHub: <https://github.com/adafruit/CircuitPython_Community_Bundle/releases>.
- Documentation is not available on ReadTheDocs at this time. See each library for any included documentation.
1.8.5 Workflows

Workflows are the process used to 1) manipulate files on the CircuitPython device and 2) interact with the serial connection to CircuitPython. The serial connection is usually used to access the REPL.

Starting with CircuitPython 3.x we moved to a USB-only workflow. Prior to that, we used the serial connection alone to do the whole workflow. In CircuitPython 7.x, a BLE workflow was added with the advantage of working with mobile devices. CircuitPython 8.x added a web workflow that works over the local network (usually Wi-Fi) and a web browser. Other clients can also use the Web REST API. Boards should clearly document which workflows are supported.

Code for workflows lives in `supervisor/shared`.

The workflow APIs are documented here.

### USB

These USB interfaces are enabled by default on boards with USB support. They are usable once the device has been plugged into a host.

##### CIRCUITPY drive

CircuitPython exposes a standard mass storage (MSC) interface to enable file manipulation over a standard interface. This interface works underneath the file system at the block level so using it excludes other types of workflows from manipulating the file system at the same time.

##### CDC serial

CircuitPython exposes one CDC USB interface for CircuitPython serial. This is a standard serial USB interface.

TODO: Document how it designates itself from the user CDC.

Setting baudrate 1200 and disconnecting will reboot into a bootloader. (Used by Arduino to trigger a reset into bootloader.)

### BLE

The BLE workflow is enabled for nRF boards. By default, to prevent malicious access, it is disabled. To connect to the BLE workflow, press the reset button while the status led blinks blue quickly after the safe mode blinks. The board will restart and broadcast the file transfer service UUID (0x0f2b) along with the board’s Creation IDs. This public broadcast is done at a lower transmit level so the devices must be closer. On connection, the device will need to pair and bond. Once bonded, the device will broadcast whenever disconnected using a rotating key rather than a static one. Non-bonded devices won’t be able to resolve it. After connection, the central device can discover two default services. One for file transfer and one for CircuitPython specifically that includes serial characteristics.

To change the default BLE advertising name without (or before) running user code, the desired name can be put in the `/env` file. The key is `CIRCUITPY_BLE_NAME`. It’s limited to approximately 30 characters depending on the port’s settings and will be truncated if longer.
File Transfer API

CircuitPython uses an open File Transfer API to enable file system access.

CircuitPython Service

The base UUID for the CircuitPython service is ADAFXXXX-4369-7263-7569-7450794686e. The XXXX is replaced by the four specific digits below. The service itself is 0001.

TX - 0002 / RX - 0003

These characteristic work just like the Nordic Uart Service (NUS) but have different UUIDs to prevent conflicts with user created NUS services.

Version - 0100

Read-only characteristic that returns the UTF-8 encoded version string.

Web

The web workflow is depends on adding Wi-Fi credentials into the /.env file. The keys are CIRCUITPY_WIFI_SSID and CIRCUITPY_WIFI_PASSWORD. Once these are defined, CircuitPython will automatically connect to the network and start the webserver used for the workflow. The webserver is on port 80 unless overridden by CIRCUITPY_WEB_API_PORT. It also enables MDNS.

Here is an example /.env:

```
# To auto-connect to Wi-Fi
CIRCUITPY_WIFI_SSID='scottswifi'
CIRCUITPY_WIFI_PASSWORD='secretpassword'

# To enable modifying files from the web. Change this too!
# Leave the User field blank in the browser.
CIRCUITPY_WEB_API_PASSWORD='passw0rd'

CIRCUITPY_WEB_API_PORT=80
```

MDNS is used to resolve circuitpython.local to a device specific hostname of the form cpy-XXXXXX.local. The XXXXX is based on network MAC address. The device also provides the MDNS service with service type _circuitpython and protocol _tcp.
HTTP

The web server is HTTP 1.1 and may use chunked responses so that it doesn’t need to precompute content length. The API generally consists of an HTTP method such as GET or PUT and a path. Requests and responses also have headers. Responses will contain a status code and status text such as 404 Not Found. This API tries to use standard status codes to encode the status of the various operations. The Mozilla Developer Network HTTP docs are a great reference.

Examples

The examples use curl, a common command line program for issuing HTTP requests. The examples below use circuitpython.local as the easiest way to work. If you have multiple active devices, you’ll want to use the specific cpy-XXXXXX.local version.

The examples also use password as the password placeholder. Replace it with your password before running the example.

/

The root welcome page links to the file system page and also displays other CircuitPython devices found using MDNS service discovery. This allows web browsers to find other devices from one. (All devices will respond to circuitpython.local so the device redirected to may vary.)

CORS

The web server will allow requests from cpy-XXXXXX.local, 127.0.0.1, the device’s IP and code. circuitpython.org. (circuitpython.local requests will be redirected to cpy-XXXXXX.local.)

File REST API

All file system related APIs are protected by HTTP basic authentication. It is NOT secure but will hopefully prevent some griefing in shared settings. The password is sent unencrypted so do not reuse a password with something important. The user field is left blank.

The password is taken from ~/.env with the key CIRCUITPY_WEB_API_PASSWORD. If this is unset, the server will respond with 403 Forbidden. When a password is set, but not provided in a request, it will respond 401 Unauthorized.

/fs/

The /fs/ page will respond with a directory browsing HTML once authenticated. This page is always gzipped. If the Accept: application/json header is provided, then the JSON representation of the root will be returned.
OPTIONS

When requested with the OPTIONS method, the server will respond with CORS related headers. Most aren’t needed for API use. They are there for the web browser.

- Access-Control-Allow-Methods - Varies with USB state. GET, OPTIONS when USB is active. GET, OPTIONS, PUT, DELETE, MOVE otherwise.

Example:

curl -v -u :passw0rd -X OPTIONS -L --location-trusted http://circuitpython.local/fs/

/fs/<directory path>/

Directory paths must end with a /. Otherwise, the path is assumed to be a file.

GET

Returns a JSON representation of the directory.

- 200 OK - Directory exists and JSON returned
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 404 Not Found - Missing directory

Returns information about each file in the directory:

- name - File name. No trailing / on directory names
- directory - true when a directory. false otherwise
- modified_ns - File modification time in nanoseconds since January 1st, 1970. May not use full resolution
- file_size - File size in bytes. 0 for directories

Example:


```json
[
    {
        "name": "world.txt",
        "directory": false,
        "modified_ns": 946934328000000000,
        "file_size": 12
    }
]
```
PUT

Tries to make a directory at the given path. Request body is ignored. The custom X-Timestamp header can provide a timestamp in milliseconds since January 1st, 1970 (to match JavaScript’s file time resolution) used for the directories modification time. The RTC time will used otherwise.

Returns:

- 204 No Content - Directory exists
- 201 Created - Directory created
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 409 Conflict - USB is active and preventing file system modification
- 404 Not Found - Missing parent directory
- 500 Server Error - Other, unhandled error

Example:

curl -v -u :passw0rd -X PUT -L --location-trusted http://circuitpython.local/fs/lib/hello/world/

Move

Moves the directory at the given path to X-Destination. Also known as rename.

The custom X-Destination header stores the destination path of the directory.

Returns:

- 201 Created - Directory renamed
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 404 Not Found - Source directory not found or destination path is missing
- 409 Conflict - USB is active and preventing file system modification
- 412 Precondition Failed - The destination path is already in use

Example:


DELETE

Deletes the directory and all of its contents.

Returns:

- 204 No Content - Directory and its contents deleted
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 404 Not Found - No directory
• **409** Conflict - USB is active and preventing file system modification

Example:
```
curl -v -u :passw0rd -X DELETE -L --location-trusted http://circuitpython.local/fs/lib/...hello2/world/
```

`/fs/<file path>`

**PUT**

Stores the provided content to the file path.

The custom X-Timestamp header can provide a timestamp in milliseconds since January 1st, 1970 (to match JavaScript's file time resolution) used for the directories modification time. The RTC time will used otherwise.

Returns:
```
• **201** Created - File created and saved
• **204** No Content - File existed and overwritten
• **401** Unauthorized - Incorrect password
• **403** Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
• **404** Not Found - Missing parent directory
• **409** Conflict - USB is active and preventing file system modification
• **413** Payload Too Large - Expect header not sent and file is too large
• **417** Expectation Failed - Expect header sent and file is too large
• **500** Server Error - Other, unhandled error
```

If the client sends the Expect header, the server will reply with **100** Continue when ok.

Example:
```
echo "Hello world" >> test.txt
curl -v -u :passw0rd -T test.txt -L --location-trusted http://circuitpython.local/fs/lib/...hello/world.txt
```

**GET**

Returns the raw file contents. Content-Type will be set based on extension:
```
• text/plain - .py, .txt
• text/javascript - .js
• text/html - .html
• application/json - .json
• application/octet-stream - Everything else
```

Will return:
```
• **200** OK - File exists and file returned
```
MOVE

Moves the file at the given path to the X-Destination. Also known as rename.

The custom X-Destination header stores the destination path of the file.

- 201 Created - File renamed
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 404 Not Found - Source file not found or destination path is missing
- 409 Conflict - USB is active and preventing file system modification
- 412 Precondition Failed - The destination path is already in use

Example:
```
```

DELETE

Deletes the file.

- 204 No Content - File existed and deleted
- 401 Unauthorized - Incorrect password
- 403 Forbidden - No CIRCUITPY_WEB_API_PASSWORD set
- 404 Not Found - File not found
- 409 Conflict - USB is active and preventing file system modification

Example:
```
curl -v -u :passw0rd -X DELETE -L --location-trusted http://circuitpython.local/fs/lib/hello/world2.txt
```
/cp/

/cp/ serves basic info about the CircuitPython device and others discovered through MDNS. It is not protected by basic auth in case the device is someone else's.

Only GET requests are supported and will return 405 Method Not Allowed otherwise.

/cp/devices.json

Returns information about other devices found on the network using MDNS.

- **total**: Total MDNS response count. May be more than in devices if internal limits were hit.
- **devices**: List of discovered devices.
  - hostname: MDNS hostname
  - instance_name: MDNS instance name. Defaults to human readable board name.
  - port: Port of CircuitPython Web API
  - ip: IP address

Example:

curl -v -L http://circuitpython.local/cp/devices.json

```
{
    "total": 1,
    "devices": [
        {
            "hostname": "cpy-951032",
            "instance_name": "Adafruit Feather ESP32-S2 TFT",
            "port": 80,
            "ip": "192.168.1.235"
        }
    ]
}
```

/cp/serial/

Serves a basic serial terminal program when a GET request is received without the Upgrade: websocket header. Otherwise the socket is upgraded to a WebSocket. See WebSockets below for more detail.

This is an authenticated endpoint in both modes.
/cp/version.json

Returns information about the device.

- web_api_version: Always 1. This versions the rest of the API and new versions may not be backwards compatible.
- version: CircuitPython build version.
- build_date: CircuitPython build date.
- board_name: Human readable name of the board.
- mcu_name: Human readable name of the microcontroller.
- board_id: Board id used in code and on circuitpython.org.
- creator_id: Creator ID for the board.
- creation_id: Creation ID for the board, set by the creator.
- hostname: MDNS hostname.
- port: Port of CircuitPython Web Service.
- ip: IP address of the device.

Example:

```
curl -v -L http://circuitpython.local/cp/version.json
```

```
{
    "web_api_version": 1,
    "version": "8.0.0-alpha.1-20-geld4518a9-dirty",
    "build_date": "2022-06-24",
    "board_name": "ESP32-S3-USB-OTG-N8",
    "mcu_name": "ESP32S3",
    "board_id": "espressif_esp32s3_usb_otg_n8",
    "creator_id": 12346,
    "creation_id": 28683,
    "hostname": "cpy-f57ce8",
    "port": 80,
    "ip": "192.168.1.94"
}
```

/code/

The /code/ page returns a small static html page that will pull in and load the full code editor from code.circuitpython.org for a full code editor experience. Because most of the resources reside online instead of the device, an active internet connection is required.
The CircuitPython serial interactions are available over a WebSocket. A WebSocket begins as a special HTTP request that gets upgraded to a WebSocket. Authentication happens before upgrading.

WebSockets are not bare sockets once upgraded. Instead they have their own framing format for data. CircuitPython can handle PING and CLOSE opcodes. All others are treated as TEXT. Data to CircuitPython is expected to be masked UTF-8, as the spec requires. Data from CircuitPython to the client is unmasked. It is also unbuffered so the client will get a variety of frame sizes.

Only one WebSocket at a time is supported.

### 1.8.6 Environment Variables

CircuitPython 8.0.0 introduces support for environment variables. Environment variables are commonly used to store “secrets” such as Wi-Fi passwords and API keys. This method does not make them secure. It only separates them from the code.

CircuitPython supports these by mimicking the dotenv CPython library. Other languages such as Javascript, PHP and Ruby also have dotenv libraries.

These libraries store environment variables in a `.env` file. Here is a simple example:

```bash
KEY1=value1
# Comment
KEY2=value2
is multiple lines
```

CircuitPython uses the `.env` at the drive root (no folder) as the environment. User code can access the values from the file using `os.getenv()`. It is recommended to save any values used repeatedly in a variable because `os.getenv()` will parse the `.env` on every access.

### CircuitPython behavior

CircuitPython will also read the environment to configure its behavior. Other keys are ignored by CircuitPython. Here are the keys it uses:
CIRCUITPY_BLE_NAME

Default BLE name the board advertises as, including for the BLE workflow.

CIRCUITPY_RESERVED_PSRAM

On boards with Espressif microcontrollers with PSRAM (also called SPIRAM), permanently reserve a portion of PSRAM for use by esp-idf. This storage is removed from the CircuitPython “heap” and is available for allocation by esp-idf routines in the core instead. Generally, only set this to a non-zero value when it is required by a specific core module.

CIRCUITPY_WEB_API_PASSWORD

Password required to make modifications to the board from the Web Workflow.

CIRCUITPY_WEB_API_PORT

TCP port number used for the web HTTP API. Defaults to 80 when omitted.

CIRCUITPY_WIFI_PASSWORD

Wi-Fi password used to auto connect to CIRCUITPY_WIFI_SSID.

CIRCUITPY_WIFI_SSID

Wi-Fi SSID to auto-connect to even if user code is not running.

1.8.7 Design Guide

This guide covers a variety of development practices for CircuitPython core and library APIs. These APIs are both built-into CircuitPython and those that are distributed on GitHub and in the Adafruit and Community bundles. Consistency with these practices ensures that beginners can learn a pattern once and apply it throughout the CircuitPython ecosystem.

Start libraries with the cookiecutter

Cookiecutter is a tool that lets you bootstrap a new repo based on another repo. We’ve made one here for CircuitPython libraries that include configs for Travis CI and ReadTheDocs along with a setup.py, license, code of conduct, readme among other files.

Cookiecutter will provide a series of prompts relating to the library and then create a new directory with all of the files. See the CircuitPython cookiecutter README for more details.
Module Naming

Adafruit funded libraries should be under the adafruit organization and have the format Adafruit_CircuitPython_<name> and have a corresponding adafruit_<name> directory (aka package) or adafruit_<name>.py file (aka module).

If the name would normally have a space, such as “Thermal Printer”, use an underscore instead (“Thermal_Printer”). This underscore will be used everywhere even when the separation between “adafruit” and “circuitpython” is done with a -. Use the underscore in the cookiecutter prompts.

Community created libraries should have the repo format CircuitPython_<name> and not have the adafruit_ module or package prefix.

Both should have the CircuitPython repository topic on GitHub.

Terminology

As our Code of Conduct states, we strive to use “welcoming and inclusive language.” Whether it is in documentation or in code, the words we use matter. This means we disfavor language that due to historical and social context can make community members and potential community members feel unwelcome.

There are specific terms to avoid except where technical limitations require it. While specific cases may call for other terms, consider using these suggested terms first:

<table>
<thead>
<tr>
<th>Preferred</th>
<th>Deprecated</th>
</tr>
</thead>
<tbody>
<tr>
<td>Main (device)</td>
<td>Master</td>
</tr>
<tr>
<td>Peripheral</td>
<td>Slave</td>
</tr>
<tr>
<td>Sensor</td>
<td></td>
</tr>
<tr>
<td>Secondary (device)</td>
<td></td>
</tr>
<tr>
<td>Denylist</td>
<td>Blacklist</td>
</tr>
<tr>
<td>Allowlist</td>
<td>Whitelist</td>
</tr>
</tbody>
</table>

Note that “technical limitations” refers e.g., to the situation where an upstream library or URL has to contain those substrings in order to work. However, when it comes to documentation and the names of parameters and properties in CircuitPython, we will use alternate terms even if this breaks tradition with past practice.

Lifetime and ContextManagers

A driver should be initialized and ready to use after construction. If the device requires deinitialization, then provide it through deinit() and also provide __enter__ and __exit__ to create a context manager usable with with.

For example, a user can then use deinit():

```python
import digitalio
import board
import time

led = digitalio.DigitalInOut(board.LED)
led.direction = digitalio.Direction.OUTPUT

for i in range(10):
    led.value = True
    time.sleep(0.5)
```

(continues on next page)
This will deinit the underlying hardware at the end of the program as long as no exceptions occur.

Alternatively, using a with statement ensures that the hardware is deinitialized:

```python
import digitalio
import board
import time

with digitalio.DigitalInOut(board.LED) as led:
    led.direction = digitalio.Direction.OUTPUT

    for i in range(10):
        led.value = True
        time.sleep(0.5)

    led.value = False
    time.sleep(0.5)
```

Python’s with statement ensures that the deinit code is run regardless of whether the code within the with statement executes without exceptions.

For small programs like the examples this isn’t a major concern because all user usable hardware is reset after programs are run or the REPL is run. However, for more complex programs that may use hardware intermittently and may also handle exceptions on their own, deinitializing the hardware using a with statement will ensure hardware isn’t enabled longer than needed.

### Verify your device

Whenever possible, make sure the device you are talking to is the device you expect. If not, raise a RuntimeError. Beware that I2C addresses can be identical on different devices so read registers you know to make sure they match your expectation. Validating this upfront will help catch mistakes.

### Getters/Setters

When designing a driver for a device, use properties for device state and use methods for sequences of abstract actions that the device performs. State is a property of the device as a whole that exists regardless of what the code is doing. This includes things like temperature, time, sound, light and the state of a switch. For a more complete list see the sensor properties bullet below.

Another way to separate state from actions is that state is usually something the user can sense themselves by sight or feel for example. Actions are something the user can watch. The device does this and then this.

Making this separation clear to the user will help beginners understand when to use what.

Here is more info on properties from Python.
Exceptions and asserts

Raise an appropriate Exception, along with a useful message, whenever a critical test or other condition fails.

Example:

```python
if not 0 <= pin <= 7:
    raise ValueError("Pin number must be 0-7."
```

If memory is constrained and a more compact method is needed, use The assert statement instead.

Example:

```python
assert 0 <= pin <= 7, "Pin number must be 0-7."
```

Design for compatibility with CPython

CircuitPython is aimed to be one’s first experience with code. It will be the first step into the world of hardware and software. To ease one’s exploration out from this first step, make sure that functionality shared with CPython shares the same API. It doesn’t need to be the full API, it can be a subset. However, do not add non-CPython APIs to the same modules. Instead, use separate non-CPython modules to add extra functionality. By distinguishing API boundaries at modules you increase the likelihood that incorrect expectations are found on import and not randomly during runtime.

When adding a new module for additional functionality related to a CPython module do NOT simply prefix it with u. This is not a large enough differentiation from CPython. This is the MicroPython convention and they use u* modules interchangeably with the CPython name. This is confusing. Instead, think up a new name that is related to the extra functionality you are adding.

For example, storage mounting and unmounting related functions were moved from uos into a new storage module. These names better match their functionality and do not conflict with CPython names. Make sure to check that you don’t conflict with CPython libraries too. That way we can port the API to CPython in the future.

Example

When adding extra functionality to CircuitPython to mimic what a normal operating system would do, either copy an existing CPython API (for example file writing) or create a separate module to achieve what you want. For example, mounting and unmounting drives is not a part of CPython so it should be done in a module, such as a new storage module, that is only available in CircuitPython. That way when someone moves the code to CPython they know what parts need to be adapted.

Document inline

Whenever possible, document your code right next to the code that implements it. This makes it more likely to stay up to date with the implementation itself. Use Sphinx’s automodule to format these all nicely in ReadTheDocs. The cookiecutter helps set these up.

Use Sphinx flavor rST for markup.

Lots of documentation is a good thing but it can take a lot of space. To minimize the space used on disk and on load, distribute the library as both .py and .mpy, MicroPython and CircuitPython’s bytecode format that omits comments.
Module description

After the license comment:

```python
""
`<module name>`
=================================================================

<Longer description>

* Author(s):

Implementation Notes
---------------------

**Hardware:**

* `Adafruit Device Description` _ (Product ID: <Product Number>)

**Software and Dependencies:**

* Adafruit CircuitPython firmware for the supported boards:
  https://circuitpython.org/downloads

* Adafruit's Bus Device library:
  https://github.com/adafruit/Adafruit_CircuitPython_BusDevice

* Adafruit's Register library:
  https://github.com/adafruit/Adafruit_CircuitPython_Register

""

Class description

At the class level document what class does and how to initialize it:

```python
class DS3231:
    """DS3231 real-time clock.

    :param ~busio.I2C i2c_bus: The I2C bus the DS3231 is connected to.
    :param int address: The I2C address of the device. Defaults to :const:`0x40`
    """

def __init__(self, i2c_bus, address=0x40):
    self._i2c = i2c_bus
```

Renders as:

```python
class DS3231(i2c_bus, address=64)
    DS3231 real-time clock.
```
Parameters

- **i2c_bus** (**I2C**) – The I2C bus the DS3231 is connected to.
- **address** (**int**) – The I2C address of the device. Defaults to **0x40**

Documenting Parameters

Although there are different ways to document class and functions definitions in Python, the following is the prevalent method of documenting parameters for CircuitPython libraries. When documenting class parameters you should use the following structure:

```python
:param param_type param_name: Parameter_description
```

**param_type**

The type of the parameter. This could be, among others, **int**, **float**, **str**, **bool**, etc. To document an object in the CircuitPython domain, you need to include a `~` before the definition as shown in the following example:

```python
:param ~busio.I2C i2c_bus: The I2C bus the DS3231 is connected to.
```

To include references to CircuitPython modules, cookiecutter creates an entry in the `intersphinx_mapping` section in the `conf.py` file located within the `docs` directory. To add different types outside CircuitPython you need to include them in the `intersphinx_mapping`:

```python
intersphinx_mapping = {
    "python": ("https://docs.python.org/3.4", None),
    "CircuitPython": ("https://circuitpython.readthedocs.io/en/latest/", None),
}
```

The `intersphinx_mapping` above includes references to Python, BusDevice and CircuitPython Documentation

When the parameter have two different types, you should reference them as follows:

```python
class Character_LCD:
    ""
    Base class for character LCD
    
    :param ~digitalio.DigitalInOut rs: The reset data line
    :param ~pwmio.PWMOut,~digitalio.DigitalInOut blue: Blue RGB Anode
    ""

def __init__(self, rs, blue):
    self._rc = rs
    self.blue = blue
```

This renders as:

```python
class Character_LCD(rs, blue)
    Base class for character LCD

    Parameters
```

Renders as:

```python
class Character_LCD:
    
    Parameters
```
• **rs** (*DigitalInOut*) – The reset data line

• **blue** (*PWMOut, DigitalInOut*) – Blue RGB Anode

### param_name

Parameter name used in the class or method definition

### Parameter_description

Parameter description. When the parameter defaults to a particular value, it is good practice to include the default:

```bash
:param int pitch: Pitch value for the servo. Defaults to :const:`4500`
```

### Attributes

Attributes are state on objects. (See *Getters/Setters* above for more discussion about when to use them.) They can be defined internally in a number of different ways. Each approach is enumerated below with an explanation of where the comment goes.

Regardless of how the attribute is implemented, it should have a short description of what state it represents including the type, possible values and/or units. It should be marked as *(read-only)* or *(write-only)* at the end of the first line for attributes that are not both readable and writable.

### Instance attributes

Comment comes from after the assignment:

```python
def __init__(self, drive_mode):
    self.drive_mode = drive_mode
    
    """
    The pin drive mode. One of:
    - `digitalio.DriveMode.PUSH_PULL`
    - `digitalio.DriveMode.OPEN_DRAIN`
    """
```

Renders as:

**drive_mode**

The pin drive mode. One of:

- `digitalio.DriveMode.PUSH_PULL`
- `digitalio.DriveMode.OPEN_DRAIN`
**Property description**

Comment comes from the getter:

```python
@property
def datetime(self):
    """The current date and time as a `time.struct_time`."""
    return self.datetime_register

@datetime.setter
def datetime(self, value):
    pass
```

Renders as:

```text
datetime

The current date and time as a `time.struct_time`.
```

Read-only example:

```python
@property
def temperature(self):
    """The current temperature in degrees Celsius. (read-only)
    The device may require calibration to get accurate readings."""
    return self._read(TEMPERATURE)
```

Renders as:

```text
temperature

The current temperature in degrees Celsius. (read-only)
The device may require calibration to get accurate readings.
```

**Data descriptor description**

Comment is after the definition:

```python
lost_power = i2c_bit.RWBit(0x0f, 7)
""""""True if the device has lost power since the time was set."""
```

Renders as:

```text
lost_power

True if the device has lost power since the time was set.
```
Method description

First line after the method definition:

```python
def turn_right(self, degrees):
    """Turns the bot `degrees` right.

    :param float degrees: Degrees to turn right
    """
```

Renders as:

```python
turn_right(degrees)
    Turns the bot degrees right.

Parameters

degrees (float) – Degrees to turn right
```

Documentation References to other Libraries

When you need to make references to documentation in other libraries you should refer the class using single backticks `adafruit_motor.servo.Servo`. You must also add the reference in the conf.py file in the intersphinx_mapping section by adding a new entry:

```text
```

Use `adafruit_register` when possible

`Register` is a foundational library that manages packing and unpacking data from I2C device registers. There is also `RegisterSPI` for SPI devices. When possible, use one of these libraries for unpacking and packing registers. This ensures the packing code is shared amongst all registers (even across drivers). Furthermore, it simplifies device definitions by making them declarative (only data.)

Values with non-consecutive bits in a register or that represent FIFO endpoints may not map well to existing register classes. In unique cases like these, it is ok to read and write the register directly.

_Do not_ add all registers from a datasheet upfront. Instead, only add the ones necessary for the functionality the driver exposes. Adding them all will lead to unnecessary file size and API clutter. See this video about outside-in design from @tannewt.

I2C Example

```python
from adafruit_register import i2c_bit
from adafruit_bus_device import i2c_device

class HelloWorldDevice:
    """Device with two bits to control when the words 'hello' and 'world' are lit."""

    hello = i2c_bit.RWBit(0x0, 0x0)
    """Bit to indicate if hello is lit."""
```
world = i2c_bit.RWBit(0x1, 0x0)
"""Bit to indicate if world is lit."""

def __init__(self, i2c, device_address=0x0):
    self.i2c_device = i2c_device.I2CDevice(i2c, device_address)

Use BusDevice

BusDevice is an awesome foundational library that manages talking on a shared I2C or SPI device for you. The devices manage locking which ensures that a transfer is done as a single unit despite CircuitPython internals and, in the future, other Python threads. For I2C, the device also manages the device address. The SPI device, manages baudrate settings, chip select line and extra post-transaction clock cycles.

I2C Example

from adafruit_bus_device import i2c_device

DEVICE_DEFAULT_I2C_ADDR = 0x42
class Widget:
    """A generic widget."""
    def __init__(self, i2c, address=DEVICE_DEFAULT_I2C_ADDR):
        self.i2c_device = i2c_device.I2CDevice(i2c, address)
        self.buf = bytearray(1)

        @property
        def register(self):
            """Widget's one register."""
            with self.i2c_device as i2c:
                i2c.writeto(b'0x00')
                i2c.readfrom_into(self.buf)
            return self.buf[0]

SPI Example

from adafruit_bus_device import spi_device
class SPIWidget:
    """A generic widget with a weird baudrate."""
    def __init__(self, spi, chip_select):
        # chip_select is a pin reference such as board.D10.
        self.spi_device = spi_device.SPIDevice(spi, chip_select, baudrate=12345)
        self.buf = bytearray(1)

        @property
def register(self):
    """Widget's one register."""
    with self.spi_device as spi:
        spi.write(b'0x00')
        spi.readinto(self.buf)
    return self.buf[0]

Class documentation example template

When documenting classes, you should use the following template to illustrate basic usage. It is similar with the simplest example, however this will display the information in the Read The Docs documentation. The advantage of using this template is it makes the documentation consistent across the libraries.

This is an example for a AHT20 temperature sensor. Include the following after the class parameter:

"""
**Quickstart: Importing and using the AHT10/AHT20 temperature sensor**

Here is an example of using the :class:`AHTx0` class. First you will need to import the libraries to use the sensor

.. code-block:: python

    import board
    import adafruit_ahtx0

Once this is done you can define your `board.I2C` object and define your sensor object

.. code-block:: python

    i2c = board.I2C()  # uses board.SCL and board.SDA
    aht = adafruit_ahtx0.AHTx0(i2c)

Now you have access to the temperature and humidity using the :attr:`temperature` and :attr:`relative_humidity` attributes

.. code-block:: python

    temperature = aht.temperature
    relative_humidity = aht.relative_humidity

"""
Use composition

When writing a driver, take in objects that provide the functionality you need rather than taking their arguments and constructing them yourself or subclassing a parent class with functionality. This technique is known as composition and leads to code that is more flexible and testable than traditional inheritance.

See also:

Wikipedia has more information on “dependency inversion”.

For example, if you are writing a driver for an I2C device, then take in an I2C object instead of the pins themselves. This allows the calling code to provide any object with the appropriate methods such as an I2C expansion board.

Another example is to expect a `DigitalInOut` for a pin to toggle instead of a `Pin` from `board`. Taking in the `Pin` object alone would limit the driver to pins on the actual microcontroller instead of pins provided by another driver such as an IO expander.

Lots of small modules

CircuitPython boards tend to have a small amount of internal flash and a small amount of ram but large amounts of external flash for the file system. So, create many small libraries that can be loaded as needed instead of one large file that does everything.

Speed second

Speed isn’t as important as API clarity and code size. So, prefer simple APIs like properties for state even if it sacrifices a bit of speed.

Avoid allocations in drivers

Although Python doesn’t require managing memory, it’s still a good practice for library writers to think about memory allocations. Avoid them in drivers if you can because you never know how much something will be called. Fewer allocations means less time spent cleaning up. So, where you can, prefer bytearray buffers that are created in `__init__` and used throughout the object with methods that read or write into the buffer instead of creating new objects. Unified hardware API classes such as `busio.SPI` are design to read and write to subsections of buffers.

It’s ok to allocate an object to return to the user. Just beware of causing more than one allocation per call due to internal logic.

However, this is a memory tradeoff so do not do it for large or rarely used buffers.

Examples

`struct.pack`

Use `struct.pack_into` instead of `struct.pack`. 
Use of MicroPython `const()`

The MicroPython `const()` feature, as discussed in this forum post, and in this issue thread, provides some optimizations that can be useful on smaller, memory constrained devices. However, when using `const()`, keep in mind these general guidelines:

- Always use via an import, ex: `from micropython import const`
- Limit use to global (module level) variables only.
- Only used when the user will not need access to variable and prefix name with a leading underscore, ex: `_SOME_CONST`.

Example

```python
from adafruit_bus_device import i2c_device
from micropython import const

_DEFAULT_I2C_ADDR = const(0x42)

class Widget:
    """A generic widget."""
    def __init__(self, i2c, address=_DEFAULT_I2C_ADDR):
        self.i2c_device = i2c_device.I2CDevice(i2c, address)
```

Libraries Examples

When adding examples, cookiecutter will add a `<name>_simpletest.py` file in the examples directory for you. Be sure to include code with the library minimal functionalities to work on a device. You could other examples if needed featuring different functionalities of the library. If you add additional examples, be sure to include them in the `examples.rst`. Naming of the examples files should use the name of the library followed by a description, using underscore to separate them. When using print statements you should use the "\"".format() format, as there are particular boards that are not capable to use f-strings.

```python
text_to_display = "World!"

print("Hello {}".format(text_to_display))
```

Sensor properties and units

The Adafruit Unified Sensor Driver Arduino library has a great list of measurements and their units. Use the same ones including the property name itself so that drivers can be used interchangeably when they have the same properties.
<table>
<thead>
<tr>
<th>Property name</th>
<th>Python type</th>
<th>Units</th>
</tr>
</thead>
<tbody>
<tr>
<td>acceleration</td>
<td>(float, float)</td>
<td>x, y, z meter per second per second</td>
</tr>
<tr>
<td>magnetic</td>
<td>(float, float)</td>
<td>x, y, z micro-Tesla (uT)</td>
</tr>
<tr>
<td>orientation</td>
<td>(float, float)</td>
<td>x, y, z degrees</td>
</tr>
<tr>
<td>gyro</td>
<td>(float, float)</td>
<td>x, y, z radians per second</td>
</tr>
<tr>
<td>temperature</td>
<td>float</td>
<td>degrees Celsius</td>
</tr>
<tr>
<td>C02</td>
<td>float</td>
<td>measured CO2 in ppm</td>
</tr>
<tr>
<td>eCO2</td>
<td>float</td>
<td>equivalent/estimated CO2 in ppm (estimated from some other measurement)</td>
</tr>
<tr>
<td>TVOC</td>
<td>float</td>
<td>Total Volatile Organic Compounds in ppb</td>
</tr>
<tr>
<td>distance</td>
<td>float</td>
<td>centimeters (cm)</td>
</tr>
<tr>
<td>proximity</td>
<td>int</td>
<td>non-unit-specific proximity values (monotonic but not actual distance)</td>
</tr>
<tr>
<td>light</td>
<td>float</td>
<td>non-unit-specific light levels (should be monotonic but is not lux)</td>
</tr>
<tr>
<td>lux</td>
<td>float</td>
<td>SI lux</td>
</tr>
<tr>
<td>pressure</td>
<td>float</td>
<td>hectopascal (hPa)</td>
</tr>
<tr>
<td>relative_humidity</td>
<td>float</td>
<td>percent</td>
</tr>
<tr>
<td>current</td>
<td>float</td>
<td>milliamps (mA)</td>
</tr>
<tr>
<td>voltage</td>
<td>float</td>
<td>volts (V)</td>
</tr>
<tr>
<td>color</td>
<td>int</td>
<td>RGB, eight bits per channel (0xff0000 is red)</td>
</tr>
<tr>
<td>alarm</td>
<td>(time.struct, str)</td>
<td>Sample alarm time and string to characterize frequency such as “hourly”</td>
</tr>
<tr>
<td>datetime</td>
<td>time.struct</td>
<td>date and time</td>
</tr>
<tr>
<td>duty_cycle</td>
<td>int</td>
<td>16-bit PWM duty cycle (regardless of output resolution)</td>
</tr>
<tr>
<td>frequency</td>
<td>int</td>
<td>Hertz (Hz)</td>
</tr>
<tr>
<td>value</td>
<td>bool</td>
<td>Digital logic</td>
</tr>
<tr>
<td>value</td>
<td>int</td>
<td>16-bit Analog value, unit-less</td>
</tr>
<tr>
<td>weight</td>
<td>float</td>
<td>grams (g)</td>
</tr>
<tr>
<td>sound_level</td>
<td>float</td>
<td>non-unit-specific sound level (monotonic but not actual decibels)</td>
</tr>
</tbody>
</table>

**Driver constant naming**

When adding variables for constant values for a driver. Do not include the device’s name in the variable name. For example, in adafruit_fancy123.py, variables should not start with FANCY123_. Adding this prefix increases RAM usage and .mpy file size because variable names are preserved. User code should refer to these constants as adafruit_fancy123.HELLO_WORLD for clarity. adafruit_fancy123.FANCY123 HELLO WORLD would be overly verbose.

**Adding native modules**

The Python API for a new module should be defined and documented in shared-bindings and define an underlying C API. If the implementation is port-agnostic or relies on underlying APIs of another module, the code should live in shared-module. If it is port specific then it should live in common-hal within the port’s folder. In either case, the file and folder structure should mimic the structure in shared-bindings.

To test your native modules or core enhancements, follow these Adafruit Learning Guides for building local firmware to flash onto your device(s):

Build CircuitPython
MicroPython compatibility

Keeping compatibility with MicroPython isn’t a high priority. It should be done when it’s not in conflict with any of the above goals.

We love CircuitPython and would love to see it come to more microcontroller platforms. Since 3.0 we’ve reworked CircuitPython to make it easier than ever to add support. While there are some major differences between ports, this page covers the similarities that make CircuitPython what it is and how that core fits into a variety of microcontrollers.

1.8.8 Architecture

There are three core pieces to CircuitPython:

The first is the Python VM that the awesome MicroPython devs have created. These VMs are written to be portable so there is not much needed when moving to a different microcontroller, especially if it is ARM based.

The second is the infrastructure around those VMs which provides super basic operating system functionality such as initializing hardware, running USB, prepping file systems and automatically running user code on boot. In CircuitPython we’ve dubbed this component the supervisor because it monitors and facilitates the VMs which run user Python code. Porting involves the supervisor because many of the tasks it does while interfacing with the hardware. Once complete, the REPL works and debugging can migrate to a Python based approach rather than C.

The third core piece is the plethora of low level APIs that CircuitPython provides as the foundation for higher level libraries including device drivers. These APIs are called from within the running VMs through the Python interfaces defined in shared-bindings. These bindings rely on the underlying common_hal C API to implement the functionality needed for the Python API. By splitting the two, we work to ensure standard functionality across which means that libraries and examples apply across ports with minimal changes.

1.8.9 Porting

Step 1: Getting building

The first step to porting to a new microcontroller is getting a build running. The primary goal of it should be to get main.c compiling with the assistance of the supervisor/supervisor.mk file. Port specific code should be isolated to the port’s directory (in the top level until the ports directory is present). This includes the Makefile and any C library resources. Make sure these resources are compatible with the MIT License of the rest of the code!

Circuitpython has a number of modules enabled by default in py/circuitpy_mpconfig.mk. Most of these modules will need to be disabled in mpconfigboard.mk during the early stages of a port in order for it to compile. As the port progresses in module support, this list can be pruned down as a natural “TODO” list. An example minimal build list is shown below:

```bash
# These modules are implemented in ports/<port>/common-hal:

# Typically the first module to create
CIRCUITY_MICROCONTROLLER = 0
# Typically the second module to create
CIRCUITY_DIGITALIO = 0
# Other modules:
CIRCUITY_ANALOGIO = 0
CIRCUITY_BUSIO = 0
CIRCUITY_COUNTIO = 0
CIRCUITY_NEOPIXEL_WRITE = 0
CIRCUITY_PULSEIO = 0
```

(continues on next page)
Step 2: Init

Once your build is setup, the next step should be to get your clocks going as you expect from the supervisor. The supervisor calls `port_init` to allow for initialization at the beginning of main. This function also has the ability to request a safe mode state which prevents the supervisor from running user code while still allowing access to the REPL and other resources.

The core port initialization and reset methods are defined in `supervisor/port.c` and should be the first to be implemented. It’s required that they be implemented in the `supervisor` directory within the port directory. That way, they are always in the expected place.

The supervisor also uses three linker variables, `_ezero`, `_estack` and `_ebss` to determine memory layout for stack overflow checking.
Step 3: REPL

Getting the REPL going is a huge step. It involves a bunch of initialization to be done correctly and is a good sign you are well on your porting way. To get the REPL going you must implement the functions and definitions from supervisor/serial.h with a corresponding supervisor/serial.c in the port directory. This involves sending and receiving characters over some sort of serial connection. It could be UART or USB for example.

1.8.10 Adding *io support to other ports

digitalio provides a well-defined, cross-port hardware abstraction layer built to support different devices and their drivers. It’s backed by the Common HAL, a C api suitable for supporting different hardware in a similar manner. By sharing this C api, developers can support new hardware easily and cross-port functionality to the new hardware.

These instructions also apply to analogio, busio, pulseio and touchio. Most drivers depend on analogio, digitalio and busio so start with those.

File layout

Common HAL related files are found in these locations:

- shared-bindings Shared home for the Python <-> C bindings which includes inline RST documentation for the created interfaces. The common hal functions are defined in the .h files of the corresponding C files.
- shared-module Shared home for C code built on the Common HAL and used by all ports. This code only uses common_hal methods defined in shared-bindings.
- <port>/common-hal Port-specific implementation of the Common HAL.

Each folder has the substructure of / and they should match 1:1. __init__.c is used for module globals that are not classes (similar to __init__.py).

Adding support

Modifying the build

The first step is to hook the shared-bindings into your build for the modules you wish to support. Here’s an example of this step for the atmel-samd/Makefile:

```
SRC_BINDINGS = \
  board/__init__.c \
  microcontroller/__init__.c \
  microcontroller/Pin.c \
  analogio/__init__.c \
  analogio/AnalogIn.c \
  analogio/AnalogOut.c \
  digitalio/__init__.c \
  digitalio/DigitalInOut.c \
  pulseio/__init__.c \
  pulseio/PulseIn.c \
  pulseio/PulseOut.c \
  pulseio/PWMOut.c \
  busio/__init__.c \
  busio/I2C.c \
```

(continues on next page)
The `Makefile` defines the modules to build and adds the sources to include the shared-bindings version and the common-hal version within the ports specific directory. You may comment out certain subfolders to reduce the number of modules to add but don’t comment out individual classes. It won’t compile then.

**Hooking the modules in**

Built in modules are typically defined in `mpconfigport.h`. To add support you should have something like:

```c
extern const struct _mp_obj_module_t microcontroller_module;
extern const struct _mp_obj_module_t analogio_module;
extern const struct _mp_obj_module_t digitalio_module;
extern const struct _mp_obj_module_t pulseio_module;
extern const struct _mp_obj_module_t busio_module;
extern const struct _mp_obj_module_t board_module;
extern const struct _mp_obj_module_t time_module;
extern const struct _mp_obj_module_t neopixel_write_module;

#define MICROPY_PORT_BUILTIN_MODULES
    { MP_OBJ_NEW_QSTR(MP_QSTR_microcontroller), (mp_obj_t)&microcontroller_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_analogio), (mp_obj_t)&analogio_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_digitalio), (mp_obj_t)&digitalio_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_pulseio), (mp_obj_t)&pulseio_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_busio), (mp_obj_t)&busio_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_board), (mp_obj_t)&board_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_time), (mp_obj_t)&time_module },,
    { MP_OBJ_NEW_QSTR(MP_QSTR_neopixel_write),(mp_obj_t)&neopixel_write_module }
```
Implementing the Common HAL

At this point in the port, nothing will compile yet, because there’s still work to be done to fix missing sources, compile issues, and link issues. I suggest start with a common-hal directory from another port that implements it such as atmel-samd or esp8266, deleting the function contents and stubbing out any return statements. Once that is done, you should be able to compile cleanly and import the modules, but nothing will work (though you are getting closer).

The last step is actually implementing each function in a port specific way. I can’t help you with this. :-) If you have any questions how a Common HAL function should work then see the corresponding .h file in shared-bindings.

Testing

Woohoo! You are almost done. After you implement everything, lots of drivers and sample code should just work.

There are a number of drivers and examples written for Adafruit’s Feather ecosystem. Here are places to start:

- Adafruit repos with CircuitPython topic
- Adafruit driver bundle

1.8.11 MicroPython libraries

Python standard libraries and micro-libraries

The libraries below are inherited from MicroPython. They are similar to the standard Python libraries with the same name. They implement a subset of or a variant of the corresponding standard Python library.

CircuitPython’s long-term goal is that code written in CircuitPython using Python standard libraries will be runnable on CPython without changes.

These libraries are not enabled on CircuitPython builds with limited flash memory, usually on non-Express builds: binascii, errno, json, re.

These libraries are not currently enabled in any CircuitPython build, but may be in the future: ctypes

builtins – builtin functions and exceptions

All builtin functions and exceptions are described here. They are also available via the builtins module.

For more information about built-ins, see the following CPython documentation:

- Builtin CPython Functions
- Builtin CPython Exceptions
- Builtin CPython Constants

Note: Not all of these functions, types, exceptions, and constants are turned on in all CircuitPython ports, for space reasons.
Functions and types

builtins.abs()
builtins.all()
builtins.any()
builtins.bin()
class builtins.bool
class builtins.bytearray
class builtins.bytes
    See CPython documentation: bytes.
builtins.callable()
builtins.chr()
builtins.classmethod()
builtins.compile()
class builtins.complex
builtins.delattr(obj, name)
    The argument name should be a string, and this function deletes the named attribute from the object given by obj.
class builtins.dict
builtins.dir()
builtins.divmod()
builtins.enumerate()
builtins.eval()
builtins.exec()
builtins.filter()
class builtins.float
class builtins.frozenset
    frozenset() is not enabled on non-Express CircuitPython boards.
builtins.getattr()
builtins.globals()
builtins.hasattr()
builtins.hash()
builtins.hex()
CircuitPython Documentation, Release 8.0.0-beta.4

builtins.id()
builtins.input()
class builtins.int

    classmethod from_bytes(bytes, byteorder)
    In CircuitPython, byteorder parameter must be positional (this is compatible with CPython).

to_bytes(size, byteorder)
    In CircuitPython, byteorder parameter must be positional (this is compatible with CPython).
builtins.isinstance()
builtins.issubclass()
builtins.iter()
builtins.len()
class builtins.list
builtinslocals()
builtins.map()
builtins.max()
class builtins.memoryview
builtins.min()
builtins.next()
class builtins.object
builtins.oct()
builtins.open()
builtins.ord()
builtins.pow()
builtins.print()
builtins.property()
builtins.range()
builtins.repr()
builtins.reversed()

reversed() is not enabled on non-Express CircuitPython boards.
builtins.round()
class builtins.set
builtinssetattr()
class builtins.slice

    The *slice* builtin is the type that slice objects have.

builtins.sorted()
builtins.staticmethod()
class builtins.str
builtins.sum()
builtins.super()
class builtins.tuple
builtins.type()
builtins.zip()

**Exceptions**

exception builtins.ArithmeticError
exception builtins.AssertionError
exception builtins.AttributeError
exception builtins.BaseException
exception builtins.BrokenPipeError
exception builtins.ConnectionError
exception builtins.EOFError
exception builtins.Exception
exception builtins.ImportError
exception builtins.indentationError
exception builtins.IndexError
exception builtins.KeyboardInterrupt
exception builtins.KeyError
exception builtins.LookupError
exception builtins.MemoryError
exception builtins.NameError
exception builtins.NotImplementedError
exception builtins.OSError
exception builtins.OverflowError
exception builtins.RuntimeError

exception builtins.ReloadException

    ReloadException is used internally to deal with soft restarts.

    Not a part of the CPython standard library

exception builtins.StopAsyncIteration

exception builtins.StopIteration

exception builtins.SyntaxError

exception builtins.SystemExit

exception builtins.TimeoutError

exception builtins.TypeError

exception builtins.UnicodeError

exception builtins=ValueError

exception builtins.ZeroDivisionError

Constants

builtins.Ellipsis

builtins.NotImplemented

heapq – heap queue algorithm

Warning: Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: heapq.

This module implements the min heap queue algorithm.

A heap queue is essentially a list that has its elements stored in such a way that the first item of the list is always the smallest.
Functions

heapq.heappush(heap, item)
Push the item onto the heap.

heapq.heappop(heap)
Pop the first item from the heap, and return it. Raise IndexError if heap is empty.
The returned item will be the smallest item in the heap.

heapq.heappify(x)
Convert the list x into a heap. This is an in-place operation.

array – arrays of numeric data

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: array.
Supported format codes: b, B, h, H, i, I, l, L, q, Q, f, d (the latter 2 depending on the floating-point support).

Classes

class array.array(typecode[, iterable])
Create array with elements of given type. Initial contents of the array are given by an iterable. If it is not provided, an empty array is created.

append(val)
Append new element val to the end of array, growing it.

extend(iterable)
Append new elements as contained in iterable to the end of array, growing it.

binascii – binary/ASCII conversions

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: binascii.
This module implements conversions between binary data and various encodings of it in ASCII form (in both directions).

Functions

binascii.hexlify(data[, sep])
Convert the bytes in the data object to a hexadecimal representation. Returns a bytes object.
If the additional argument sep is supplied it is used as a separator between hexadecimal values.

binascii.unhexlify(data)
Convert hexadecimal data to binary representation. Returns bytes string. (i.e. inverse of hexlify)
binascii.a2b_base64(data)
    Decode base64-encoded data, ignoring invalid characters in the input. Conforms to RFC 2045 6.8. Returns a bytes object.

binascii.b2a_base64(data)
    Encode binary data in base64 format, as in RFC 3548. Returns the encoded data followed by a newline character, as a bytes object.

binascii.crc32(data, value=0, /)
    Compute CRC-32, the 32-bit checksum of the bytes in data starting with an initial CRC of value. The default initial CRC is 0. The algorithm is consistent with the ZIP file checksum.

collections – collection and container types

Warning: Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: collections.

This module implements advanced collection and container types to hold/accumulate various objects.

Classes

collections.deque(iterable, maxlen[, flags])
    Deques (double-ended queues) are a list-like container that support O(1) appends and pops from either side of the deque. New deques are created using the following arguments:
    • iterable must be the empty tuple, and the new deque is created empty.
    • maxlen must be specified and the deque will be bounded to this maximum length. Once the deque is full, any new items added will discard items from the opposite end.
    • The optional flags can be 1 to check for overflow when adding items.

As well as supporting bool and len, deque objects have the following methods:

deque.append(x)
    Add x to the right side of the deque. Raises IndexError if overflow checking is enabled and there is no more room left.

deque.popleft()
    Remove and return an item from the left side of the deque. Raises IndexError if no items are present.

collections.namedtuple(name, fields)
    This is factory function to create a new namedtuple type with a specific name and set of fields. A namedtuple is a subclass of tuple which allows to access its fields not just by numeric index, but also with an attribute access syntax using symbolic field names. Fields is a sequence of strings specifying field names. For compatibility with CPython it can also be a a string with space-separated field named (but this is less efficient). Example of use:
from collections import namedtuple

MyTuple = namedtuple("MyTuple", ("id", "name"))
t1 = MyTuple(1, "foo")
t2 = MyTuple(2, "bar")
print(t1.name)
assert t2.name == t2[1]

collections.OrderedDict(...)
dict type subclass which remembers and preserves the order of keys added. When ordered dict is iterated over, keys/items are returned in the order they were added:

from collections import OrderedDict

# To make benefit of ordered keys, OrderedDict should be initialized
# from sequence of (key, value) pairs.
d = OrderedDict([("z", 1), ("a", 2)])
# More items can be added as usual
d["w"] = 5
d["b"] = 3
for k, v in d.items():
    print(k, v)

Output:

z 1
a 2
w 5
b 3

erro - system error codes

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: errno.

This module provides access to symbolic error codes for OSError exception. A particular inventory of codes depends on MicroPython port.

Constants

EEXIST, EAGAIN, etc.

Error codes, based on ANSI C/POSIX standard. All error codes start with “E”. As mentioned above, inventory of the codes depends on MicroPython port. Errors are usually accessible as exc.args[0] where exc is an instance of OSError. Usage example:

try:
    os.mkdir("my_dir")
except OSError as exc:
    if exc.args[0] == errno.EEXIST:
        print("Directory already exists")
**errno.errorcode**

Dictionary mapping numeric error codes to strings with symbolic error code (see above):

```python
>>> print(errno.errorcode[errno.EEXIST])
EEXIST
```

**gc – control the garbage collector**

**Warning**: Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: gc.

**Functions**

**gc.enable()**

Enable automatic garbage collection.

**gc.disable()**

Disable automatic garbage collection. Heap memory can still be allocated, and garbage collection can still be initiated manually using `gc.collect()`.

**gc.collect()**

Run a garbage collection.

**gc.mem_alloc()**

Return the number of bytes of heap RAM that are allocated.

**Difference to CPython**

This function is a MicroPython extension.

**gc.mem_free()**

Return the number of bytes of available heap RAM, or -1 if this amount is not known.

**Difference to CPython**

This function is a MicroPython extension.

**gc.threshold([amount])**

Set or query the additional GC allocation threshold. Normally, a collection is triggered only when a new allocation cannot be satisfied, i.e. on an out-of-memory (OOM) condition. If this function is called, in addition to OOM, a collection will be triggered each time after `amount` bytes have been allocated (in total, since the previous time such an amount of bytes have been allocated). `amount` is usually specified as less than the full heap size, with the intention to trigger a collection earlier than when the heap becomes exhausted, and in the hope that an
early collection will prevent excessive memory fragmentation. This is a heuristic measure, the effect of which will vary from application to application, as well as the optimal value of the amount parameter.

Calling the function without argument will return the current value of the threshold. A value of -1 means a disabled allocation threshold.

**Difference to CPython**

This function is a MicroPython extension. CPython has a similar function - set_threshold(), but due to different GC implementations, its signature and semantics are different.

**io – input/output streams**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: io.

This module contains additional types of stream (file-like) objects and helper functions.

**Conceptual hierarchy**

**Difference to CPython**

Conceptual hierarchy of stream base classes is simplified in MicroPython, as described in this section.

(Abstract) base stream classes, which serve as a foundation for behavior of all the concrete classes, adhere to few dichotomies (pair-wise classifications) in CPython. In MicroPython, they are somewhat simplified and made implicit to achieve higher efficiencies and save resources.

An important dichotomy in CPython is unbuffered vs buffered streams. In MicroPython, all streams are currently unbuffered. This is because all modern OSes, and even many RTOSes and filesystem drivers already perform buffering on their side. Adding another layer of buffering is counter-productive (an issue known as “bufferbloat”) and takes precious memory. Note that there still cases where buffering may be useful, so we may introduce optional buffering support at a later time.

But in CPython, another important dichotomy is tied with “bufferedness” - it’s whether a stream may incur short read/writes or not. A short read is when a user asks e.g. 10 bytes from a stream, but gets less, similarly for writes. In CPython, unbuffered streams are automatically short operation susceptible, while buffered are guaranteed against them. The no short read/writes is an important trait, as it allows to develop more concise and efficient programs - something which is highly desirable for MicroPython. So, while MicroPython doesn’t support buffered streams, it still provides for no-short-operations streams. Whether there will be short operations or not depends on each particular class’ needs, but developers are strongly advised to favor no-short-operations behavior for the reasons stated above. For example, MicroPython sockets are guaranteed to avoid short read/writes. Actually, at this time, there is no example of a short-operations stream class in the core, and one would be a port-specific class, where such a need is governed by hardware peculiarities.

The no-short-operations behavior gets tricky in case of non-blocking streams, blocking vs non-blocking behavior being another CPython dichotomy, fully supported by MicroPython. Non-blocking streams never wait for data either to arrive or be written - they read/write whatever possible, or signal lack of data (or ability to write data). Clearly, this conflicts with “no-short-operations” policy, and indeed, a case of non-blocking buffered (and this no-short-ops) streams is convoluted in CPython - in some places, such combination is prohibited, in some it’s undefined or just not documented, in some cases it raises verbose exceptions. The matter is much simpler in MicroPython: non-blocking stream are important for efficient asynchronous operations, so this property prevails on the “no-short-ops” one. So,
while blocking streams will avoid short reads/writes whenever possible (the only case to get a short read is if end of file is reached, or in case of error (but errors don’t return short data, but raise exceptions)), non-blocking streams may produce short data to avoid blocking the operation.

The final dichotomy is binary vs text streams. MicroPython of course supports these, but while in CPython text streams are inherently buffered, they aren’t in MicroPython. (Indeed, that’s one of the cases for which we may introduce buffering support.)

Note that for efficiency, MicroPython doesn’t provide abstract base classes corresponding to the hierarchy above, and it’s not possible to implement, or subclass, a stream class in pure Python.

**Functions**

```python
io.open(name, mode='r', **kwargs)
```

Open a file. Builtin `open()` function is aliased to this function. All ports (which provide access to file system) are required to support `mode` parameter, but support for other arguments vary by port.

**Classes**

```python
class io.FileIO(...)
```

This is type of a file open in binary mode, e.g. using `open(name, "rb")`. You should not instantiate this class directly.

```python
class io.TextIOWrapper(...)
```

This is type of a file open in text mode, e.g. using `open(name, "rt")`. You should not instantiate this class directly.

```python
class io.StringIO([string])
```

```python
class io.BytesIO([string])
```

In-memory file-like objects for input/output. `StringIO` is used for text-mode I/O (similar to a normal file opened with “t” modifier). `BytesIO` is used for binary-mode I/O (similar to a normal file opened with “b” modifier). Initial contents of file-like objects can be specified with `string` parameter (should be normal string for `StringIO` or bytes object for `BytesIO`). All the usual file methods like `read()`, `write()`, `seek()`, `flush()`, `close()` are available on these objects, and additionally, a following method:

```python
getvalue()
```

Get the current contents of the underlying buffer which holds data.

**json – JSON encoding and decoding**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: json.

This modules allows to convert between Python objects and the JSON data format.
**Functions**

`json.dumps(obj)`  
Serialise `obj` to a JSON string, writing it to the given `stream`.

`json.loads(str)`  
Parse the JSON `str` and return an object. Raises `ValueError` if the string is not correctly formed.

**re – simple regular expressions**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: `re`.

This module implements regular expression operations. Regular expression syntax supported is a subset of CPython `re` module (and actually is a subset of POSIX extended regular expressions).

Supported operators and special sequences are:

- `.`  
  Match any character.

- `[^a-c]`  
  Match set of characters. Individual characters and ranges are supported, including negated sets (e.g. `[^a-c]`).

- `^`  
  Match the start of the string.

- `$`  
  Match the end of the string.

- `?`  
  Match zero or one of the previous sub-pattern.

- `*`  
  Match zero or more of the previous sub-pattern.

- `+`  
  Match one or more of the previous sub-pattern.

- `??`  
  Non-greedy version of `?`, match zero or one, with the preference for zero.

- `*??`  
  Non-greedy version of `*`, match zero or more, with the preference for the shortest match.

- `+??`  
  Non-greedy version of `+`, match one or more, with the preference for the shortest match.

- `|`  
  Match either the left-hand side or the right-hand side sub-patterns of this operator.
Grouping. Each group is capturing (a substring it captures can be accessed with `match.group()` method).

`\d`
Matches digit. Equivalent to `[0-9]`.

`\D`
Matches non-digit. Equivalent to `[^0-9]`.

`\s`
Matches whitespace. Equivalent to `[\t-\r]`.

`\S`
Matches non-whitespace. Equivalent to `[^\t-\r]`.

`\w`
Matches “word characters” (ASCII only). Equivalent to `[A-Za-z0-9_]`.

`\W`
Matches non “word characters” (ASCII only). Equivalent to `[^A-Za-z0-9_]`.

`\`
Escape character. Any other character following the backslash, except for those listed above, is taken literally. For example, `\*` is equivalent to literal `*` (not treated as the `*` operator). Note that `\r`, `\n`, etc. are not handled specially, and will be equivalent to literal letters `r`, `n`, etc. Due to this, it’s not recommended to use raw Python strings (`r""`) for regular expressions. For example, `r"\r\n"` when used as the regular expression is equivalent to "rn". To match CR character followed by LF, use "\r\n".

**NOT SUPPORTED:**
- counted repetitions ({m,n})
- named groups ((?P<name>...))
- non-capturing groups ((?:...))
- more advanced assertions (`\b`, `\B`)
- special character escapes like `\r`, `\n` - use Python’s own escaping instead
- etc.

Example:

```python
import re

# As re doesn't support escapes itself, use of r"" strings is not # recommended.
regex = re.compile("\[\r\n"]

regex.split("line1\rline2\nline3\r\n")

# Result:
# ['line1', 'line2', 'line3', '', '']
```
Functions

**re.compile(regex_str[, flags])**

Compile regular expression, return *regex* object.

**re.match(regex_str, string)**

Compile *regex_str* and match against *string*. Match always happens from starting position in a string.

**re.search(regex_str, string)**

Compile *regex_str* and search it in *string*. Unlike *match*, this will search string for first position which matches *regex* (which still may be 0 if *regex* is anchored).

**re.sub(regex_str, replace, string, count=0, flags=0, /)**

Compile *regex_str* and search for it in *string*, replacing all matches with *replace*, and returning the new string. *replace* can be a string or a function. If it is a string then escape sequences of the form \<number> and \g<number> can be used to expand to the corresponding group (or an empty string for unmatched groups). If *replace* is a function then it must take a single argument (the match) and should return a replacement string.

If *count* is specified and non-zero then substitution will stop after this many substitutions are made. The *flags* argument is ignored.

Note: availability of this function depends on *MicroPython port*.

**re.DEBUG**

Flag value, display debug information about compiled expression. (Availability depends on *MicroPython port*.)

Regex objects

Compiled regular expression. Instances of this class are created using *re.compile()*.

**regex.match(string)**

**regex.search(string)**

**regex.sub(replace, string, count=0, flags=0, /)**

Similar to the module-level functions *match()* and *search()* and *sub(). Using methods is (much) more efficient if the same regex is applied to multiple strings.

**regex.split(string, max_split=-1, /)**

Split a *string* using *regex*. If *max_split* is given, it specifies maximum number of splits to perform. Returns list of strings (there may be up to *max_split+1* elements if it’s specified).

Match objects

Match objects as returned by *match()* and *search()* methods, and passed to the replacement function in *sub()*.

**match.group(index)**

Return matching (sub)string. *index* is 0 for entire match, 1 and above for each capturing group. Only numeric groups are supported.

**match.groups()**

Return a tuple containing all the substrings of the groups of the match.

Note: availability of this method depends on *MicroPython port*.

**match.start([index])**
match.end(index)

Return the index in the original string of the start or end of the substring group that was matched. index defaults to the entire group, otherwise it will select a group.

Note: availability of these methods depends on MicroPython port.

match.span(index)

Returns the 2-tuple (match.start(index), match.end(index)).

Note: availability of this method depends on MicroPython port.

**sys – system specific functions**

**Warning:** Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: sys.

**Functions**

sys.exit(retval=0,)

Terminate current program with a given exit code. Underlyingly, this function raise as SystemExit exception. If an argument is given, its value given as an argument to SystemExit.

**Constants**

sys.argv

A mutable list of arguments the current program was started with.

sys.byteorder

The byte order of the system ("little" or "big").

sys.implementation

Object with information about the current Python implementation. For CircuitPython, it has following attributes:

- name - string “circuitpython”
- version - tuple (major, minor, micro), e.g. (1, 7, 0)

This object is the recommended way to distinguish CircuitPython from other Python implementations (note that it still may not exist in the very minimal ports).

**Difference to CPython**

CPython mandates more attributes for this object, but the actual useful bare minimum is implemented in Circuit-Python.
sys.maxsize

Maximum value which a native integer type can hold on the current platform, or maximum value representable by CircuitPython integer type, if it’s smaller than platform max value (that is the case for CircuitPython ports without long int support).

This attribute is useful for detecting “bitness” of a platform (32-bit vs 64-bit, etc.). It’s recommended to not compare this attribute to some value directly, but instead count number of bits in it:

```python
bits = 0
v = sys.maxsize
while v:
    bits += 1
    v >>= 1
if bits > 32:
    # 64-bit (or more) platform
    ...
else:
    # 32-bit (or less) platform
    # Note that on 32-bit platform, value of bits may be less than 32
    # (e.g. 31) due to peculiarities described above, so use "-> 16",
    # "-> 32", "-> 64" style of comparisons.
```

differences to CPython

On MicroPython, an entry with the value ".frozen" will indicate that import should search frozen modules at that point in the search. If no frozen module is found then search will not look for a directory called .frozen, instead it will continue with the next entry in sys.path.

sys.platform

The platform that CircuitPython is running on. For OS/RTOS ports, this is usually an identifier of the OS, e.g. "linux". For baremetal ports it is an identifier of the chip on a board, e.g. "Microchip SAMD51". It thus can be used to distinguish one board from another. If you need to check whether your program runs on CircuitPython (vs other Python implementation), use sys.implementation instead.

sys.stderr

Standard error stream.

sys.stdin

Standard input stream.

sys.stdout

Standard output stream.

sys.version

Python language version that this implementation conforms to, as a string.

sys.version_info

Python language version that this implementation conforms to, as a tuple of ints.
Difference to CPython

Only the first three version numbers (major, minor, micro) are supported and they can be referenced only by index, not by name.

**uasyncio — asynchronous I/O scheduler**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: [asyncio](https://docs.python.org/3/library/asyncio.html)

Example:

```python
import uasyncio

async def blink(led, period_ms):
    while True:
        led.on()
        await uasyncio.sleep_ms(5)
        led.off()
        await uasyncio.sleep_ms(period_ms)

async def main(led1, led2):
    uasyncio.create_task(blink(led1, 700))
    uasyncio.create_task(blink(led2, 400))
    await uasyncio.sleep_ms(10000)

# Running on a pyboard
from pyb import LED
uasyncio.run(main(LED(1), LED(2)))

# Running on a generic board
from machine import Pin
uasyncio.run(main(Pin(1), Pin(2)))
```

**Core functions**

- **uasyncio.create_task(coro)**
  - Create a new task from the given coroutine and schedule it to run.
  - Returns the corresponding `Task` object.

- **uasyncio.current_task()**
  - Return the `Task` object associated with the currently running task.

- **uasyncio.run(coro)**
  - Create a new task from the given coroutine and run it until it completes.
  - Returns the value returned by `coro`.

- **uasyncio.sleep(t)**
  - Sleep for $t$ seconds (can be a float).
  - This is a coroutine.
**uasyncio.sleep_ms(t)**
Sleep for \( t \) milliseconds.
This is a coroutine, and a MicroPython extension.

### Additional functions

**uasyncio.wait_for(awitable, timeout)**
Wait for the `awitable` to complete, but cancel it if it takes longer than `timeout` seconds. If `awitable` is not a task then a task will be created from it.
If a timeout occurs, it cancels the task and raises `asyncio.TimeoutError`: this should be trapped by the caller.
Returns the return value of `awitable`.
This is a coroutine.

**uasyncio.wait_for_ms(awitable, timeout)**
Similar to `wait_for` but `timeout` is an integer in milliseconds.
This is a coroutine, and a MicroPython extension.

**uasyncio.gather(*awaitables, return_exceptions=False)**
Run all `awaitables` concurrently. Any `awaitables` that are not tasks are promoted to tasks.
Returns a list of return values of all `awaitables`.
This is a coroutine.

### class Task

**class uasyncio.Task**
This object wraps a coroutine into a running task. Tasks can be waited on using `await task`, which will wait for the task to complete and return the return value of the task.
Tasks should not be created directly, rather use `create_task` to create them.

**Task.cancel()**
Cancel the task by injecting a `CancelledError` into it. The task may or may not ignore this exception.

### class Event

**class uasyncio.Event**
Create a new event which can be used to synchronise tasks. Events start in the cleared state.

**Event.is_set()**
Returns `True` if the event is set, `False` otherwise.

**Event.set()**
Set the event. Any tasks waiting on the event will be scheduled to run.

**Event.clear()**
Clear the event.
Event.wait()

Wait for the event to be set. If the event is already set then it returns immediately.
This is a coroutine.

class Lock

class uasyncio.Lock

Create a new lock which can be used to coordinate tasks. Locks start in the unlocked state.
In addition to the methods below, locks can be used in an async with statement.
Lock.locked()

Returns True if the lock is locked, otherwise False.
Lock.acquire()

Wait for the lock to be in the unlocked state and then lock it in an atomic way. Only one task can acquire the lock at any one time.
This is a coroutine.
Lock.release()

Release the lock. If any tasks are waiting on the lock then the next one in the queue is scheduled to run and the lock remains locked. Otherwise, no tasks are waiting an the lock becomes unlocked.

TCP stream connections

uasyncio.open_connection(host, port)

Open a TCP connection to the given host and port. The host address will be resolved using socket.getaddrinfo, which is currently a blocking call.
Returns a pair of streams: a reader and a writer stream. Will raise a socket-specific OSError if the host could not be resolved or if the connection could not be made.
This is a coroutine.

uasyncio.start_server(callback, host, port, backlog=5)

Start a TCP server on the given host and port. The callback will be called with incoming, accepted connections, and be passed 2 arguments: reader and writer streams for the connection.
Returns a Server object.
This is a coroutine.

class uasyncio.Stream

This represents a TCP stream connection. To minimise code this class implements both a reader and a writer, and both StreamReader and StreamWriter alias to this class.

Stream.get_extra_info(v)

Get extra information about the stream, given by v. The valid values for v are: peername.

Stream.close()

Close the stream.
Stream.wait_closed()
    Wait for the stream to close.
    This is a coroutine.
Stream.read(n)
    Read up to $n$ bytes and return them.
    This is a coroutine.
Stream.readinto(buf)
    Read up to $n$ bytes into `buf` with $n$ being equal to the length of `buf`.
    Return the number of bytes read into `buf`.
    This is a coroutine, and a MicroPython extension.
Stream.readexactly(n)
    Read exactly $n$ bytes and return them as a bytes object.
    Raises an EOFError exception if the stream ends before reading $n$ bytes.
    This is a coroutine.
Stream.readline()
    Read a line and return it.
    This is a coroutine.
Stream.write(buf)
    Accumulated `buf` to the output buffer. The data is only flushed when Stream.drain is called. It is recommended to call Stream.drain immediately after calling this function.
Stream.drain()
    Drain (write) all buffered output data out to the stream.
    This is a coroutine.

class uasyncio.Server
    This represents the server class returned from start_server. It can be used in an async with statement to close the server upon exit.
Server.close()
    Close the server.
Server.wait_closed()
    Wait for the server to close.
    This is a coroutine.

Event Loop

uasyncio.get_event_loop()
    Return the event loop used to schedule and run tasks. See Loop.
uasyncio.new_event_loop()
    Reset the event loop and return it.
    Note: since MicroPython only has a single event loop this function just resets the loop’s state, it does not create a new one.
class uasyncio.Loop

This represents the object which schedules and runs tasks. It cannot be created, use `get_event_loop` instead.

Loop.create_task(coro)

Create a task from the given `coro` and return the new `Task` object.

Loop.run_forever()

Run the event loop until `stop()` is called.

Loop.run_until_complete(awaiter)

Run the given `awaiter` until it completes. If `awaiter` is not a task then it will be promoted to one.

Loop.stop()

Stop the event loop.

Loop.close()

Close the event loop.

Loop.set_exception_handler(handler)

Set the exception handler to call when a Task raises an exception that is not caught. The `handler` should accept two arguments: `(loop, context)`.

Loop.get_exception_handler()

Get the current exception handler. Returns the handler, or `None` if no custom handler is set.

Loop.default_exception_handler(context)

The default exception handler that is called.

Loop.call_exception_handler(context)

Call the current exception handler. The argument `context` is passed through and is a dictionary containing keys: 'message', 'exception', 'future'.

uctypes – access binary data in a structured way

This module implements “foreign data interface” for MicroPython. The idea behind it is similar to CPython’s `ctypes` modules, but the actual API is different, streamlined and optimized for small size. The basic idea of the module is to define data structure layout with about the same power as the C language allows, and then access it using familiar dot-syntax to reference sub-fields.

Warning: `uctypes` module allows access to arbitrary memory addresses of the machine (including I/O and control registers). Uncareful usage of it may lead to crashes, data loss, and even hardware malfunction.

See also:

Module `struct`

Standard Python way to access binary data structures (doesn’t scale well to large and complex structures).

Usage examples:

```python
import uctypes

# Example 1: Subset of ELF file header
# https://wikipedia.org/wiki/Executable_and_Linkable_Format#File_header
ELF_HEADER = {
```
"EI_MAG": (0x0 | uctypes.ARRAY, 4 | uctypes.UINT8),
"EI_DATA": 0x5 | uctypes.UINT8,
"e_machine": 0x12 | uctypes.UINT16,
}

# "f" is an ELF file opened in binary mode
buf = f.read(uctypes.sizeof(ELF_HEADER, uctypes.LITTLE_ENDIAN))
header = uctypes.struct(uctypes.addressof(buf), ELF_HEADER, uctypes.LITTLE_ENDIAN)
assert header.EI_MAG == b"\x7fELF"
assert header.EI_DATA == 1, "Oops, wrong endianness. Could retry with uctypes.BIG_ENDIAN."
print("machine:", hex(header.e_machine))

# Example 2: In-memory data structure, with pointers
COORD = {
    "x": 0 | uctypes.FLOAT32,
    "y": 4 | uctypes.FLOAT32,
}

STRUCT1 = {
    "data1": 0 | uctypes.UINT8,
    "data2": 4 | uctypes.UINT32,
    "ptr": (8 | uctypes.PTR, COORD),
}

# Suppose you have address of a structure of type STRUCT1 in "addr"
# uctypes.NATIVE is optional (used by default)
struct1 = uctypes.struct(addr, STRUCT1, uctypes.NATIVE)
print("x:", struct1.ptr[0].x)

# Example 3: Access to CPU registers. Subset of STM32F4xx WWDG block
WWDG_LAYOUT = {
    "WWDG_CR": (0, {
        "WDGA": 7 << uctypes.BF_POS | 1 << uctypes.BF_LEN | uctypes.BFUINT32,
        "T": 0 << uctypes.BF_POS | 7 << uctypes.BF_LEN | uctypes.BFUINT32,
    }),
    "WWDG_CFR": (4, {
        "EWI": 9 << uctypes.BF_POS | 1 << uctypes.BF_LEN | uctypes.BFUINT32,
        "WDGTB": 7 << uctypes.BF_POS | 2 << uctypes.BF_LEN | uctypes.BFUINT32,
        "W": 0 << uctypes.BF_POS | 7 << uctypes.BF_LEN | uctypes.BFUINT32,
    }),
}

WWDG = uctypes.struct(0x40002c00, WWDG_LAYOUT)

WWDG.WWDG_CFR.WDGTB = 0b10
WWDG.WWDG_CR.WDGA = 1
print("Current counter:", WWDG.WWDG_CR.T)
Defining structure layout

Structure layout is defined by a “descriptor” - a Python dictionary which encodes field names as keys and other properties required to access them as associated values:

```
{
    "field1": <properties>,
    "field2": <properties>,
    ...
}
```

Currently, uctypes requires explicit specification of offsets for each field. Offset are given in bytes from the structure start.

Following are encoding examples for various field types:

- **Scalar types:**

  ```
  "field_name": offset | uctypes.UINT32
  ```

  in other words, the value is a scalar type identifier ORed with a field offset (in bytes) from the start of the structure.

- **Recursive structures:**

  ```
  "sub": (offset, {
    "b0": 0 | uctypes.UINT8,
    "b1": 1 | uctypes.UINT8,
  })
  ```

  i.e. value is a 2-tuple, first element of which is an offset, and second is a structure descriptor dictionary (note: offsets in recursive descriptors are relative to the structure it defines). Of course, recursive structures can be specified not just by a literal dictionary, but by referring to a structure descriptor dictionary (defined earlier) by name.

- **Arrays of primitive types:**

  ```
  "arr": (offset | uctypes.ARRAY, size | uctypes.UINT8),
  ```

  i.e. value is a 2-tuple, first element of which is ARRAY flag ORed with offset, and second is scalar element type ORed number of elements in the array.

- **Arrays of aggregate types:**

  ```
  "arr2": (offset | uctypes.ARRAY, size, {"b": 0 | uctypes.UINT8}),
  ```

  i.e. value is a 3-tuple, first element of which is ARRAY flag ORed with offset, second is a number of elements in the array, and third is a descriptor of element type.

- **Pointer to a primitive type:**

  ```
  "ptr": (offset | uctypes.PTR, uctypes.UINT8),
  ```

  i.e. value is a 2-tuple, first element of which is PTR flag ORed with offset, and second is a scalar element type.

- **Pointer to an aggregate type:**

  ```
  "ptr2": (offset | uctypes.PTR, {"b": 0 | uctypes.UINT8}),
  ```
i.e. value is a 2-tuple, first element of which is PTR flag ORed with offset, second is a descriptor of type pointed
to.

- Bitfields:

```python
"bitf0": offset | uctypes.BUINT16 | lsbit << uctypes.BF_POS | bitsize << uctypes.BF_LEN,
```

i.e. value is a type of scalar value containing given bitfield (typenames are similar to scalar types, but prefixes
with BF), ORed with offset for scalar value containing the bitfield, and further ORed with values for bit position
and bit length of the bitfield within the scalar value, shifted by BF_POS and BF_LEN bits, respectively. A
bitfield position is counted from the least significant bit of the scalar (having position of 0), and is the number
of right-most bit of a field (in other words, it’s a number of bits a scalar needs to be shifted right to extract the
bitfield).

In the example above, first a UINT16 value will be extracted at offset 0 (this detail may be important when
accessing hardware registers, where particular access size and alignment are required), and then bitfield whose
rightmost bit is lsbit bit of this UINT16, and length is bitsize bits, will be extracted. For example, if lsbit is 0 and
bitsize is 8, then effectively it will access least-significant byte of UINT16.

Note that bitfield operations are independent of target byte endianness, in particular, example above will access
least-significant byte of UINT16 in both little- and big-endian structures. But it depends on the least significant
bit being numbered 0. Some targets may use different numbering in their native ABI, but uctypes always uses
the normalized numbering described above.

Module contents

```python
class uctypes.struct(addr, descriptor, layout_type=NATIVE,)
```

Instantiate a “foreign data structure” object based on structure address in memory, descriptor (encoded as a
dictionary), and layout type (see below).

```python
uctypes.LITTLE_ENDIAN
```

Layout type for a little-endian packed structure. (Packed means that every field occupies exactly as many bytes
as defined in the descriptor, i.e. the alignment is 1).

```python
uctypes.BIG_ENDIAN
```

Layout type for a big-endian packed structure.

```python
uctypes.NATIVE
```

Layout type for a native structure - with data endianness and alignment conforming to the ABI of the system on
which MicroPython runs.

```python
uctypes.sizeof(struct, layout_type=NATIVE,)
```

Return size of data structure in bytes. The `struct` argument can be either a structure class or a specific instantiated
structure object (or its aggregate field).

```python
uctypes.addressof(obj)
```

Return address of an object. Argument should be bytes, bytearray or other object supporting buffer protocol (and
address of this buffer is what actually returned).

```python
uctypes.bytes_at(addr, size)
```

Capture memory at the given address and size as bytes object. As bytes object is immutable, memory is actually
duplicated and copied into bytes object, so if memory contents change later, created object retains original value.
uctypes.bytearray_at(addr, size)

Capture memory at the given address and size as bytearray object. Unlike bytes_at() function above, memory is captured by reference, so it can be both written too, and you will access current value at the given memory address.

uctypes.UINT8
uctypes.INT8
uctypes.UINT16
uctypes.INT16
uctypes.UINT32
uctypes.INT32
uctypes.UINT64
uctypes.INT64

Integer types for structure descriptors. Constants for 8, 16, 32, and 64 bit types are provided, both signed and unsigned.

uctypes.FLOAT32
uctypes.FLOAT64

Floating-point types for structure descriptors.

uctypes.VOID

VOID is an alias for UINT8, and is provided to conveniently define C’s void pointers: (uctypes.PTR, uctypes.VOID).

uctypes.PTR
uctypes.ARRAY

Type constants for pointers and arrays. Note that there is no explicit constant for structures, it’s implicit: an aggregate type without PTR or ARRAY flags is a structure.

Structure descriptors and instantiating structure objects

Given a structure descriptor dictionary and its layout type, you can instantiate a specific structure instance at a given memory address using uctypes.struct() constructor. Memory address usually comes from following sources:

- Predefined address, when accessing hardware registers on a baremetal system. Lookup these addresses in datasheet for a particular MCU/SoC.
- As a return value from a call to some FFI (Foreign Function Interface) function.
- From uctypes.addressof(), when you want to pass arguments to an FFI function, or alternatively, to access some data for I/O (for example, data read from a file or network socket).

Structure objects

Structure objects allow accessing individual fields using standard dot notation: my_struct.substruct1.field1. If a field is of scalar type, getting it will produce a primitive value (Python integer or float) corresponding to the value contained in a field. A scalar field can also be assigned to.

If a field is an array, its individual elements can be accessed with the standard subscript operator [] - both read and assigned to.

If a field is a pointer, it can be dereferenced using [0] syntax (corresponding to C * operator, though [0] works in C too). Subscripting a pointer with other integer values but 0 are also supported, with the same semantics as in C.
Summing up, accessing structure fields generally follows the C syntax, except for pointer dereference, when you need to use `[0]` operator instead of `*`.

**Limitations**

1. Accessing non-scalar fields leads to allocation of intermediate objects to represent them. This means that special care should be taken to layout a structure which needs to be accessed when memory allocation is disabled (e.g. from an interrupt). The recommendations are:
   - Avoid accessing nested structures. For example, instead of `mcu_registers.peripheral_a.register1`, define separate layout descriptors for each peripheral, to be accessed as `peripheral_a.register1`. Or just cache a particular peripheral: `peripheral_a = mcu_registers.peripheral_a`. If a register consists of multiple bitfields, you would need to cache references to a particular register: `reg_a = mcu_registers.peripheral_a.reg_a`.
   - Avoid other non-scalar data, like arrays. For example, instead of `peripheral_a.register[0]` use `peripheral_a.register0`. Again, an alternative is to cache intermediate values, e.g. `register0 = peripheral_a.register[0]`.

2. Range of offsets supported by the `uctypes` module is limited. The exact range supported is considered an implementation detail, and the general suggestion is to split structure definitions to cover from a few kilobytes to a few dozen of kilobytes maximum. In most cases, this is a natural situation anyway, e.g. it doesn’t make sense to define all registers of an MCU (spread over 32-bit address space) in one structure, but rather a peripheral block by peripheral block. In some extreme cases, you may need to split a structure in several parts artificially (e.g. if accessing native data structure with multi-megabyte array in the middle, though that would be a very synthetic case).

**select – wait for events on a set of streams**

This module implements a subset of the corresponding CPython module, as described below. For more information, refer to the original CPython documentation: `select`.

This module provides functions to efficiently wait for events on multiple stream objects (select streams which are ready for operations).

**Functions**

- `select.poll()`
  - Create an instance of the Poll class.

- `select.select(rlist, wlist, xlist[, timeout])`
  - Wait for activity on a set of objects.
    - This function is provided by some MicroPython ports for compatibility and is not efficient. Usage of `Poll` is recommended instead.
class Poll

Methods

poll.register(obj[, eventmask])
Register stream obj for polling. eventmask is logical OR of:
- select.POLLIN - data available for reading
- select.POLLOUT - more data can be written

Note that flags like select.POLLHUP and select.POLLERR are not valid as input eventmask (these are unsolicited events which will be returned from poll() regardless of whether they are asked for). This semantics is per POSIX.

eventmask defaults to select.POLLIN | select.POLLOUT.

It is OK to call this function multiple times for the same obj. Successive calls will update obj’s eventmask to the value of eventmask (i.e. will behave as modify()).

poll.unregister(obj)
Unregister obj from polling.

poll.modify(obj, eventmask)
Modify the eventmask for obj. If obj is not registered, OSError is raised with error of ENOENT.

poll.poll(timeout=-1, )
Wait for at least one of the registered objects to become ready or have an exceptional condition, with optional timeout in milliseconds (if timeout arg is not specified or -1, there is no timeout).

Returns list of (obj, event, ...) tuples. There may be other elements in tuple, depending on a platform and version, so don’t assume that its size is 2. The event element specifies which events happened with a stream and is a combination of select.POLL* constants described above. Note that flags select.POLLHUP and select.POLLERR can be returned at any time (even if were not asked for), and must be acted on accordingly (the corresponding stream unregistered from poll and likely closed), because otherwise all further invocations of poll() may return immediately with these flags set for this stream again.

In case of timeout, an empty list is returned.

Difference to CPython

Tuples returned may contain more than 2 elements as described above.

poll.ipoll(timeout=-1, flags=0, )
Like poll.poll(), but instead returns an iterator which yields a callee-owned tuples. This function provides efficient, allocation-free way to poll on streams.

If flags is 1, one-shot behaviour for events is employed: streams for which events happened will have their event masks automatically reset (equivalent to poll.modify(obj, 0)), so new events for such a stream won’t be processed until new mask is set with poll.modify(). This behaviour is useful for asynchronous I/O schedulers.

Difference to CPython

This function is a MicroPython extension.
Omitted functions in the string library

A few string operations are not enabled on small builds (usually non-Express), due to limited flash memory: `string.center()`, `string.partition()`, `string.splitlines()`, `string.reversed()`.

CircuitPython/MicroPython-specific libraries

Functionality specific to the CircuitPython/MicroPython implementation is available in the following libraries. These libraries may change significantly or be removed in future versions of CircuitPython.

**btree – simple BTree database**

---

**Warning:** Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

The `btree` module implements a simple key-value database using external storage (disk files, or in general case, a random-access stream). Keys are stored sorted in the database, and besides efficient retrieval by a key value, a database also supports efficient ordered range scans (retrieval of values with the keys in a given range). On the application interface side, BTree database work as close a possible to a way standard `dict` type works, one notable difference is that both keys and values must be `bytes` objects (so, if you want to store objects of other types, you need to serialize them to `bytes` first).

The module is based on the well-known BerkelyDB library, version 1.xx.

Example:

```python
import btree

# First, we need to open a stream which holds a database
# This is usually a file, but can be in-memory database
# using io.BytesIO, a raw flash partition, etc.
# Oftentimes, you want to create a database file if it doesn't
# exist and open if it exists. Idiom below takes care of this.
# DO NOT open database with "a+b" access mode.
try:
    f = open("mydb", "r+b")
except OSError:
    f = open("mydb", "w+b")

# Now open a database itself
db = btree.open(f)

# The keys you add will be sorted internally in the database
db[b"3"] = b"three"
db[b"1"] = b"one"
db[b"2"] = b"two"

# Assume that any changes are cached in memory unless
# explicitly flushed (or database closed). Flush database
```

(continues on next page)
# at the end of each "transaction".
db.flush()

# Prints b'two'
print(db[b"2"])

# Iterate over sorted keys in the database, starting from b"2"
# until the end of the database, returning only values.
# Mind that arguments passed to values() method are *key* values.
# Prints:
# b'two'
# b'three'
for word in db.values(b"2"):
    print(word)

del db[b"2"]

# No longer true, prints False
print(b"2" in db)

# Prints:
# b"1"
# b"3"
for key in db:
    print(key)

db.close()

# Don't forget to close the underlying stream!
f.close()

Functions

btree.open(stream, *, flags=0, pagesize=0, cachesize=0, minkeypage=0)

Open a database from a random-access stream (like an open file). All other parameters are optional and keyword-only, and allow to tweak advanced parameters of the database operation (most users will not need them):

• flags - Currently unused.

• pagesize - Page size used for the nodes in BTree. Acceptable range is 512-65536. If 0, a port-specific default will be used, optimized for port’s memory usage and/or performance.

• cachesize - Suggested memory cache size in bytes. For a board with enough memory using larger values may improve performance. Cache policy is as follows: entire cache is not allocated at once; instead, accessing a new page in database will allocate a memory buffer for it, until value specified by cachesize is reached. Then, these buffers will be managed using LRU (least recently used) policy. More buffers may still be allocated if needed (e.g., if a database contains big keys and/or values). Allocated cache buffers aren’t reclaimed.

• minkeypage - Minimum number of keys to store per page. Default value of 0 equivalent to 2.

Returns a BTree object, which implements a dictionary protocol (set of methods), and some additional methods described below.
Methods

btree.close()
Close the database. It’s mandatory to close the database at the end of processing, as some unwritten data may be still in the cache. Note that this does not close underlying stream with which the database was opened, it should be closed separately (which is also mandatory to make sure that data flushed from buffer to the underlying storage).

btree.flush()
Flush any data in cache to the underlying stream.

btree.__getitem__(key)
btree.get(key, default=None)  
btree.__setitem__(key, val)
btree.__delitem__(key)
btree.__contains__(key)
Standard dictionary methods.

btree.__iter__()
A BTree object can be iterated over directly (similar to a dictionary) to get access to all keys in order.

btree.keys([start_key[, end_key[, flags ]]]]
btree.values([start_key[, end_key[, flags ]]]]
btree.items([start_key[, end_key[, flags ]]]]

These methods are similar to standard dictionary methods, but also can take optional parameters to iterate over a key sub-range, instead of the entire database. Note that for all 3 methods, start_key and end_key arguments represent key values. For example, values() method will iterate over values corresponding to they key range given. None values for start_key means “from the first key’, no end_key or its value of None means “until the end of database”. By default, range is inclusive of start_key and exclusive of end_key, you can include end_key in iteration by passing flags of btree.INCL. You can iterate in descending key direction by passing flags of btree.DESC. The flags values can be ORed together.

Constants

btree.INCL
A flag for keys(), values(), items() methods to specify that scanning should be inclusive of the end key.

btree.DESC
A flag for keys(), values(), items() methods to specify that scanning should be in descending direction of keys.

framebuf — frame buffer manipulation

Warning: Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

This module provides a general frame buffer which can be used to create bitmap images, which can then be sent to a display.
class FrameBuffer

The FrameBuffer class provides a pixel buffer which can be drawn upon with pixels, lines, rectangles, text and even other FrameBuffer's. It is useful when generating output for displays.

For example:

```python
import framebuf

# FrameBuffer needs 2 bytes for every RGB565 pixel
fbuf = framebuf.FrameBuffer(bytearray(100 * 10 * 2), 100, 10, framebuf.RGB565)

fbuf.fill(0)
fbuf.text('MicroPython!', 0, 0, 0xffff)
fbuf.hline(0, 9, 96, 0xffff)
```

Constructors

class framebuf.FrameBuffer(buffer, width, height, format, stride=width, /)

Construct a FrameBuffer object. The parameters are:

- **buffer** is an object with a buffer protocol which must be large enough to contain every pixel defined by the width, height and format of the FrameBuffer.
- **width** is the width of the FrameBuffer in pixels
- **height** is the height of the FrameBuffer in pixels
- **format** specifies the type of pixel used in the FrameBuffer; permissible values are listed under Constants below. These set the number of bits used to encode a color value and the layout of these bits in `buffer`. Where a color value `c` is passed to a method, `c` is a small integer with an encoding that is dependent on the format of the FrameBuffer.
- **stride** is the number of pixels between each horizontal line of pixels in the FrameBuffer. This defaults to `width` but may need adjustments when implementing a FrameBuffer within another larger FrameBuffer or screen. The `buffer` size must accommodate an increased step size.

One must specify valid `buffer`, `width`, `height`, `format` and optionally `stride`. Invalid `buffer` size or dimensions may lead to unexpected errors.

Drawing primitive shapes

The following methods draw shapes onto the FrameBuffer.

FrameBuffer.fill(c)

Fill the entire FrameBuffer with the specified color.

FrameBuffer.pixel(x, y[, c])

If `c` is not given, get the color value of the specified pixel. If `c` is given, set the specified pixel to the given color.

FrameBuffer.hline(x, y, w, c)

FrameBuffer.vline(x, y, h, c)
FrameBuffer.line\((x_1, y_1, x_2, y_2, c)\)

Draw a line from a set of coordinates using the given color and a thickness of 1 pixel. The line method draws the line up to a second set of coordinates whereas the hline and vline methods draw horizontal and vertical lines respectively up to a given length.

FrameBuffer.rect\((x, y, w, h, c)\)

FrameBuffer.fill_rect\((x, y, w, h, c)\)

Draw a rectangle at the given location, size and color. The rect method draws only a 1 pixel outline whereas the fill_rect method draws both the outline and interior.

Drawing text

FrameBuffer.text\((s, x, y, [c])\)

Write text to the FrameBuffer using the the coordinates as the upper-left corner of the text. The color of the text can be defined by the optional argument but is otherwise a default value of 1. All characters have dimensions of 8x8 pixels and there is currently no way to change the font.

Other methods

FrameBuffer.scroll\((x\text{step}, y\text{step})\)

Shift the contents of the FrameBuffer by the given vector. This may leave a footprint of the previous colors in the FrameBuffer.

FrameBuffer.blit\((fbuf, x, y, key=-1, palette=None)\)

Draw another FrameBuffer on top of the current one at the given coordinates. If key is specified then it should be a color integer and the corresponding color will be considered transparent: all pixels with that color value will not be drawn.

The palette argument enables blitting between FrameBuffers with differing formats. Typical usage is to render a monochrome or grayscale glyph/icon to a color display. The palette is a FrameBuffer instance whose format is that of the current FrameBuffer. The palette height is one pixel and its pixel width is the number of colors in the source FrameBuffer. The palette for an N-bit source needs \(2^N\) pixels; the palette for a monochrome source would have 2 pixels representing background and foreground colors. The application assigns a color to each pixel in the palette. The color of the current pixel will be that of that palette pixel whose x position is the color of the corresponding source pixel.

Constants

framebuf.MONO_VLSB

Monochrome (1-bit) color format This defines a mapping where the bits in a byte are vertically mapped with bit 0 being nearest the top of the screen. Consequently each byte occupies 8 vertical pixels. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered at locations starting at the leftmost edge, 8 pixels lower.

framebuf.MONO_HLSB

Monochrome (1-bit) color format This defines a mapping where the bits in a byte are horizontally mapped. Each byte occupies 8 horizontal pixels with bit 7 being the leftmost. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered on the next row, one pixel lower.
framebuf.MONO_HMSB
Monochrome (1-bit) color format This defines a mapping where the bits in a byte are horizontally mapped. Each byte occupies 8 horizontal pixels with bit 0 being the leftmost. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered on the next row, one pixel lower.

framebuf.RGB565
Red Green Blue (16-bit, 5+6+5) color format

framebuf.GS2_HMSB
Grayscale (2-bit) color format

framebuf.GS4_HMSB
Grayscale (4-bit) color format

framebuf.GS8
Grayscale (8-bit) color format

micropython – access and control MicroPython internals

Warning: Though this MicroPython-based library may be available for use in some builds of CircuitPython, it is unsupported and its functionality may change in the future, perhaps significantly. As CircuitPython continues to develop, it may be changed to comply more closely with the corresponding standard Python library. You will likely need to change your code later if you rely on any non-standard functionality it currently provides.

Functions

micropython.const(expr)
Used to declare that the expression is a constant so that the compile can optimise it. The use of this function should be as follows:

```python
from micropython import const
CONST_X = const(123)
CONST_Y = const(2 * CONST_X + 1)
```

Constants declared this way are still accessible as global variables from outside the module they are declared in. On the other hand, if a constant begins with an underscore then it is hidden, it is not available as a global variable, and does not take up any memory during execution.

This `const` function is recognised directly by the MicroPython parser and is provided as part of the `micropython` module mainly so that scripts can be written which run under both CPython and MicroPython, by following the above pattern.

micropython.opt_level([level])
If `level` is given then this function sets the optimisation level for subsequent compilation of scripts, and returns None. Otherwise it returns the current optimisation level.

The optimisation level controls the following compilation features:

- Assertions: at level 0 assertion statements are enabled and compiled into the bytecode; at levels 1 and higher assertions are not compiled.
- Built-in `__debug__` variable: at level 0 this variable expands to `True`; at levels 1 and higher it expands to `False`. 
• Source-code line numbers: at levels 0, 1 and 2 source-code line number are stored along with the bytecode so that exceptions can report the line number they occurred at; at levels 3 and higher line numbers are not stored.

The default optimisation level is usually level 0.

\[\text{micropython.mem_info}(\text{verbose})]\]

Print information about currently used memory. If the \textit{verbose} argument is given then extra information is printed.

The information that is printed is implementation dependent, but currently includes the amount of stack and heap used. In verbose mode it prints out the entire heap indicating which blocks are used and which are free.

\[\text{micropython.qstr_info}(\text{verbose})]\]

Print information about currently interned strings. If the \textit{verbose} argument is given then extra information is printed.

The information that is printed is implementation dependent, but currently includes the number of interned strings and the amount of RAM they use. In verbose mode it prints out the names of all RAM-interned strings.

\[\text{micropython.stack_use}()\]

Return an integer representing the current amount of stack that is being used. The absolute value of this is not particularly useful, rather it should be used to compute differences in stack usage at different points.

\[\text{micropython.heap_lock}()\]

\[\text{micropython.heap_unlock}()\]

\[\text{micropython.heap_locked}()\]

Lock or unlock the heap. When locked no memory allocation can occur and a \texttt{MemoryError} will be raised if any heap allocation is attempted. \texttt{heap_locked()} returns a true value if the heap is currently locked.

These functions can be nested, i.e. \texttt{heap_lock()} can be called multiple times in a row and the lock-depth will increase, and then \texttt{heap_unlock()} must be called the same number of times to make the heap available again.

Both \texttt{heap_unlock()} and \texttt{heap_locked()} return the current lock depth (after unlocking for the former) as a non-negative integer, with 0 meaning the heap is not locked.

If the REPL becomes active with the heap locked then it will be forcefully unlocked.

Note: \texttt{heap_locked()} is not enabled on most ports by default, requires \texttt{MICROPY_PY_MICROPYTHON_HEAP_LOCKED}.

\[\text{micropython.kbd_intr}(\texttt{chr})\]

Set the character that will raise a \texttt{KeyboardInterrupt} exception. By default this is set to 3 during script execution, corresponding to Ctrl-C. Passing -1 to this function will disable capture of Ctrl-C, and passing 3 will restore it.

This function can be used to prevent the capturing of Ctrl-C on the incoming stream of characters that is usually used for the REPL, in case that stream is used for other purposes.

\[\text{micropython.schedule}(\texttt{func, arg})\]

Schedule the function \texttt{func} to be executed “very soon”. The function is passed the value \texttt{arg} as its single argument. “Very soon” means that the MicroPython runtime will do its best to execute the function at the earliest possible time, given that it is also trying to be efficient, and that the following conditions hold:

• A scheduled function will never preempt another scheduled function.

• Scheduled functions are always executed “between opcodes” which means that all fundamental Python operations (such as appending to a list) are guaranteed to be atomic.
• A given port may define “critical regions” within which scheduled functions will never be executed. Func-
tions may be scheduled within a critical region but they will not be executed until that region is exited. An
eexample of a critical region is a preempting interrupt handler (an IRQ).

A use for this function is to schedule a callback from a preempting IRQ. Such an IRQ puts restrictions on the
code that runs in the IRQ (for example the heap may be locked) and scheduling a function to call later will lift
those restrictions.

Note: If \texttt{schedule()} is called from a preempting IRQ, when memory allocation is not allowed and the callback
to be passed to \texttt{schedule()} is a bound method, passing this directly will fail. This is because creating a reference
to a bound method causes memory allocation. A solution is to create a reference to the method in the class
constructor and to pass that reference to \texttt{schedule()}.

There is a finite queue to hold the scheduled functions and \texttt{schedule()} will raise a \texttt{RuntimeError} if the queue
is full.

1.8.12 Glossary

baremetal

A system without a (full-fledged) operating system, for example an \textit{MCU}-based system. When running on a
baremetal system, MicroPython effectively functions like a small operating system, running user programs and
providing a command interpreter (\textit{REPL}).

buffer protocol

Any Python object that can be automatically converted into bytes, such as \texttt{bytes}, \texttt{bytearray}, \texttt{memoryview} and
\texttt{str} objects, which all implement the “buffer protocol”.

board

Typically this refers to a printed circuit board (PCB) containing a \textit{microcontroller} and supporting components.
MicroPython firmware is typically provided per-board, as the firmware contains both MCU-specific functionality
but also board-level functionality such as drivers or pin names.

bytecode

A compact representation of a Python program that generated by compiling the Python source code. This is what
the VM actually executes. Bytecode is typically generated automatically at runtime and is invisible to the user.
Note that while \textit{CPython} and MicroPython both use bytecode, the format is different. You can also pre-compile
source code offline using the \textit{cross-compiler}.

callee-owned tuple

This is a MicroPython-specific construct where, for efficiency reasons, some built-in functions or methods may
re-use the same underlying tuple object to return data. This avoids having to allocate a new tuple for every call,
and reduces heap fragmentation. Programs should not hold references to callee-owned tuples and instead only
extract data from them (or make a copy).

CircuitPython

A variant of MicroPython developed by \textit{Adafruit Industries}.

CPython

CPython is the reference implementation of the Python programming language, and the most well-known one.
It is, however, one of many implementations (including Jython, IronPython, PyPy, and MicroPython). While
MicroPython’s implementation differs substantially from CPython, it aims to maintain as much compatibility as
possible.

cross-compiler

Also known as \texttt{mpy-cross}. This tool runs on your PC and converts a \texttt{.py file} containing MicroPython code into
a \texttt{.mpy file} containing MicroPython bytecode. This means it loads faster (the board doesn’t have to compile the
code), and uses less space on flash (the bytecode is more space efficient).
driver
A MicroPython library that implements support for a particular component, such as a sensor or display.

FFI
Acronym for Foreign Function Interface. A mechanism used by the MicroPython Unix port to access operating system functionality. This is not available on baremetal ports.

filesystem
Most MicroPython ports and boards provide a filesystem stored in flash that is available to user code via the standard Python file APIs such as open(). Some boards also make this internal filesystem accessible to the host via USB mass-storage.

frozen module
A Python module that has been cross compiled and bundled into the firmware image. This reduces RAM requirements as the code is executed directly from flash.

Garbage Collector
A background process that runs in Python (and MicroPython) to reclaim unused memory in the heap.

GPIO
General-purpose input/output. The simplest means to control electrical signals (commonly referred to as “pins”) on a microcontroller. GPIO typically allows pins to be either input or output, and to set or get their digital value (logical “0” or “1”). MicroPython abstracts GPIO access using the machine.Pin and machine.Signal classes.

GPIO port
A group of GPIO pins, usually based on hardware properties of these pins (e.g. controllable by the same register).

heap
A region of RAM where MicroPython stores dynamic data. It is managed automatically by the Garbage Collector. Different MCUs and boards have vastly different amounts of RAM available for the heap, so this will affect how complex your program can be.

interned string
An optimisation used by MicroPython to improve the efficiency of working with strings. An interned string is referenced by its (unique) identity rather than its address and can therefore be quickly compared just by its identifier. It also means that identical strings can be de-duplicated in memory. String interning is almost always invisible to the user.

MCU
Microcontroller. Microcontrollers usually have much less resources than a desktop, laptop, or phone, but are smaller, cheaper and require much less power. MicroPython is designed to be small and optimized enough to run on an average modern microcontroller.

MicroPython port
MicroPython supports different boards, RTOSes, and OSes, and can be relatively easily adapted to new systems. MicroPython with support for a particular system is called a “port” to that system. Different ports may have widely different functionality. This documentation is intended to be a reference of the generic APIs available across different ports (“MicroPython core”). Note that some ports may still omit some APIs described here (e.g. due to resource constraints). Any such differences, and port-specific extensions beyond the MicroPython core functionality, would be described in the separate port-specific documentation.

MicroPython Unix port
The unix port is one of the major MicroPython ports. It is intended to run on POSIX-compatible operating systems, like Linux, MacOS, FreeBSD, Solaris, etc. It also serves as the basis of Windows port. The Unix port is very useful for quick development and testing of the MicroPython language and machine-independent features. It can also function in a similar way to CPython’s python executable.

.mpy file
The output of the cross-compiler. A compiled form of a .py file that contains MicroPython bytecode instead of Python source code.
CircuitPython Documentation, Release 8.0.0-beta.4

native
Usually refers to “native code”, i.e. machine code for the target microcontroller (such as ARM Thumb, Xtensa, x86/x64). The @native decorator can be applied to a MicroPython function to generate native code instead of bytecode for that function, which will likely be faster but use more RAM.

port
Usually short for MicroPython port, but could also refer to GPIO port.

.py file
A file containing Python source code.

REPL
An acronym for “Read, Eval, Print, Loop”. This is the interactive Python prompt, useful for debugging or testing short snippets of code. Most MicroPython boards make a REPL available over a UART, and this is typically accessible on a host PC via USB.

stream
Also known as a “file-like object”. An Python object which provides sequential read-write access to the underlying data. A stream object implements a corresponding interface, which consists of methods like read(), write(), readinto(), seek(), flush(), close(), etc. A stream is an important concept in MicroPython; many I/O objects implement the stream interface, and thus can be used consistently and interchangeably in different contexts. For more information on streams in MicroPython, see the io module.

UART
Acronym for “Universal Asynchronous Receiver/Transmitter”. This is a peripheral that sends data over a pair of pins (TX & RX). Many boards include a way to make at least one of the UARTs available to a host PC as a serial port over USB.

1.8.13 CircuitPython

circuitpython.org | Get CircuitPython | Documentation | Contributing | Branding | Differences from Micropython | Project Structure

CircuitPython is a beginner friendly, open source version of Python for tiny, inexpensive computers called microcontrollers. Microcontrollers are the brains of many electronics including a wide variety of development boards used to build hobby projects and prototypes. CircuitPython in electronics is one of the best ways to learn to code because it connects code to reality. Simply install CircuitPython on a supported USB board usually via drag and drop and then edit a code.py file on the CIRCUITPY drive. The code will automatically reload. No software installs are needed besides a text editor (we recommend Mu for beginners.)

Starting with CircuitPython 7.0.0, some boards may only be connectable over Bluetooth Low Energy (BLE). Those boards provide serial and file access over BLE instead of USB using open protocols. (Some boards may use both USB and BLE.) BLE access can be done from a variety of apps including code.circuitpython.org.

CircuitPython features unified Python core APIs and a growing list of 300+ device libraries and drivers that work with it. These libraries also work on single board computers with regular Python via the Adafruit Blinka Library.
CircuitPython is based on MicroPython. See below for differences. Most, but not all, CircuitPython development is sponsored by Adafruit and is available on their educational development boards. Please support both MicroPython and Adafruit.

Get CircuitPython

Official binaries for all supported boards are available through circuitpython.org/downloads. The site includes stable, unstable and continuous builds. Full release notes are available through GitHub releases as well.

Documentation

Guides and videos are available through the Adafruit Learning System under the CircuitPython category. An API reference is also available on Read the Docs. A collection of awesome resources can be found at Awesome CircuitPython.

Specifically useful documentation when starting out:

- Welcome to CircuitPython
- CircuitPython Essentials
- Example Code

Code Search

GitHub doesn’t currently support code search on forks. Therefore, CircuitPython doesn’t have code search through GitHub because it is a fork of MicroPython. Luckily, SourceGraph has free code search for public repos like CircuitPython. So, visit sourcegraph.com/github.com/adafruit/circuitpython to search the CircuitPython codebase online.

Contributing

See CONTRIBUTING.md for full guidelines but please be aware that by contributing to this project you are agreeing to the Code of Conduct. Contributors who follow the Code of Conduct are welcome to submit pull requests and they will be promptly reviewed by project admins. Please join the Discord too.

Branding

While we are happy to see CircuitPython forked and modified, we’d appreciate it if forked releases not use the name “CircuitPython” or the Blinka logo. “CircuitPython” means something special to us and those who learn about it. As a result, we’d like to make sure products referring to it meet a common set of requirements.

If you’d like to use the term “CircuitPython” and Blinka for your product here is what we ask:

- Your product is supported by the primary “adafruit/circuitpython” repo. This way we can update any custom code as we update the CircuitPython internals.
- Your product is listed on circuitpython.org (source here). This is to ensure that a user of your product can always download the latest version of CircuitPython from the standard place.
- Your product supports at least one standard “Workflow” for serial and file access:
  - With a user accessible USB plug which appears as a CIRCUITPY drive when plugged in.
  - With file and serial access over Bluetooth Low Energy using the BLE Workflow.
  - With file access over WiFi using the WiFi Workflow with serial access over USB and/or WebSocket.
• Boards that do not support the USB Workflow should be clearly marked.

If you choose not to meet these requirements, then we ask you call your version of CircuitPython something else (for example, SuperDuperPython) and not use the Blinka logo. You can say it is “CircuitPython-compatible” if most CircuitPython drivers will work with it.

Differences from MicroPython

CircuitPython:
• Supports native USB on most boards and BLE otherwise, allowing file editing without special tools.
• Floats (aka decimals) are enabled for all builds.
• Error messages are translated into 10+ languages.
• Concurrency within Python is not well supported. Interrupts and threading are disabled. async/await keywords are available on some boards for cooperative multitasking. Some concurrency is achieved with native modules for tasks that require it such as audio file playback.

Behavior
• The order that files are run and the state that is shared between them. CircuitPython’s goal is to clarify the role of each file and make each file independent from each other.
  – boot.py runs only once on start up before workflows are initialized. This lays the ground work for configuring USB at startup rather than it being fixed. Since serial is not available, output is written to boot_out.txt.
  – code.py (or main.py) is run after every reload until it finishes or is interrupted. After it is done running, the vm and hardware is reinitialized. This means you cannot read state from code.py in the REPL anymore, as the REPL is a fresh vm. CircuitPython’s goal for this change includes reducing confusion about pins and memory being used.
  – After the main code is finished the REPL can be entered by pressing any key.
  – Autoreload state will be maintained across reload.
• Adds a safe mode that does not run user code after a hard crash or brown out. This makes it possible to fix code that causes nasty crashes by making it available through mass storage after the crash. A reset (the button) is needed after it’s fixed to get back into normal mode.
• RGB status LED indicating CircuitPython state. - One green flash - code completed without error. - Two red flashes - code ended due to an exception. - Three yellow flashes - safe mode. May be due to CircuitPython internal error.
• Re-runs code.py or other main file after file system writes by a workflow. (Disable with supervisor.default.disable_autoreload())
• Autoreload is disabled while the REPL is active.
• Main is one of these: code.txt, code.py, main.py, main.txt
• Boot is one of these: boot.py, boot.txt
API

- Unified hardware APIs. Documented on ReadTheDocs.
- API docs are Python stubs within the C files in shared-bindings.
- No machine API.

Modules

- No module aliasing. (uos and utime are not available as os and time respectively.) Instead os, time, and random are CPython compatible.
- New storage module which manages file system mounts. (Functionality from uos in MicroPython.)
- Modules with a CPython counterpart, such as time, os and random, are strict subsets of their CPython version. Therefore, code from CircuitPython is runnable on CPython but not necessarily the reverse.
- tick count is available as time.monotonic()
Ports

Ports include the code unique to a microcontroller line.

<table>
<thead>
<tr>
<th>Supported</th>
<th>Support status</th>
</tr>
</thead>
<tbody>
<tr>
<td>atmel-samd</td>
<td>SAMD21 stable</td>
</tr>
<tr>
<td>cxd56</td>
<td>stable</td>
</tr>
<tr>
<td>espressif</td>
<td>ESP32 beta</td>
</tr>
<tr>
<td>litex</td>
<td>alpha</td>
</tr>
<tr>
<td>mimxrt10xx</td>
<td>alpha</td>
</tr>
<tr>
<td>nrf</td>
<td>stable</td>
</tr>
<tr>
<td>raspberryi</td>
<td>stable</td>
</tr>
<tr>
<td>stm</td>
<td>F4 stable</td>
</tr>
<tr>
<td>unix</td>
<td>alpha</td>
</tr>
</tbody>
</table>

- **stable** Highly unlikely to have bugs or missing functionality.
- **beta** Being actively improved but may be missing functionality and have bugs.
- **alpha** Will have bugs and missing functionality.

Boards

- Each port has a boards directory containing boards which belong to a specific microcontroller line.
- A list of native modules supported by a particular board can be found here.

**1.8.14 Contributing**

Please note that this project is released with a **Contributor Code of Conduct**. By participating in this project you agree to abide by its terms. Participation covers any forum used to converse about CircuitPython including unofficial and official spaces. Failure to do so will result in corrective actions such as time out or ban from the project.

**Licensing**

By contributing to this repository you are certifying that you have all necessary permissions to license the code under an MIT License. You still retain the copyright but are granting many permissions under the MIT License.

If you have an employment contract with your employer please make sure that they don’t automatically own your work product. Make sure to get any necessary approvals before contributing. Another term for this contribution off-hours is moonlighting.
Ways to contribute

As CircuitPython grows, there are more and more ways to contribute. Here are some ideas:

• Build a project with CircuitPython and share how to do it online.
• Test the latest libraries and CircuitPython versions with your projects and file issues for any bugs you find.
• Contribute Python code to CircuitPython libraries that support new devices or features of an existing device.
• Contribute C code to CircuitPython which fixes an open issue or adds a new feature.

Getting started with C

CircuitPython developer Dan Halbert (@dhalbert) has written up build instructions using native build tools here. For SAMD21 debugging workflow tips check out this learn guide from Scott (@tannewt).

Developer contacts

Scott Shawcroft (@tannewt) is the lead developer of CircuitPython and is sponsored by Adafruit Industries LLC. Scott is usually available during US West Coast working hours. Dan Halbert (@dhalbert) and Kattni Rembor (@kattni) are also sponsored by Adafruit Industries LLC and are usually available during US East Coast daytime hours including some weekends.

They are all reachable on Discord, GitHub issues and the Adafruit support forum.

Code guidelines

We aim to keep our code and commit style compatible with MicroPython upstream. Please review their code conventions to do so. Familiarity with their design philosophy is also useful though not always applicable to CircuitPython. Furthermore, CircuitPython has a design guide that covers a variety of different topics. Please read it as well.

1.8.15 Building CircuitPython

Welcome to CircuitPython!

This document is a quick-start guide only.

Detailed guides on how to build CircuitPython can be found in the Adafruit Learn system at https://learn.adafruit.com/building-circuitpython/

Setup

Please ensure you set up your build environment appropriately, as per the guide. You will need:

• Linux: https://learn.adafruit.com/building-circuitpython/linux
• MacOS: https://learn.adafruit.com/building-circuitpython/macos
• Windows Subsystem for Linux (WSL): https://learn.adafruit.com/building-circuitpython/windows-subsystem-for-linux
Submodules

This project has a bunch of git submodules. You will need to update them regularly.
In the root folder of the CircuitPython repository, execute the following:

```
make fetch-submodules
```

Required Python Packages

Failing to install these will prevent from properly building.

```
pip3 install -r requirements-dev.txt
```

If you run into an error installing minify_html, you may need to install rust.

**mpy-cross**

As part of the build process, mpy-cross is needed to compile .py files into .mpy files. To compile (or recompile) mpy-cross:

```
make -C mpy-cross
```

### 1.8.16 Building

There a number of ports of CircuitPython! To build for your board, change to the appropriate ports directory and build.
Examples:

```
cd ports/atmel-samd
make BOARD=circuitplayground_express
```

```
cd ports/nrf
make BOARD=circuitplayground_bluefruit
```

If you aren’t sure what boards exist, have a peek in the boards subdirectory of your port. If you have a fast computer with many cores, consider adding `-j` to your build flags, such as `-j17` on a 6-core 12-thread machine.

### 1.8.17 Testing

If you are working on changes to the core language, you might find it useful to run the test suite. The test suite in the top level `tests` directory. It needs the unix port to run.

```
cd ports/unix
make axtls
make micropython
```

Then you can run the test suite:

```
cd ../../tests
./run-tests.py
```
A successful run will say something like

```
676 tests performed (19129 individual testcases)
676 tests passed
30 tests skipped: buffered_writer builtin_help builtin_range_binop class_delattr_setattr,...
  cmd_parsetree extra_coverage framebuf1 framebuf16 framebuf2 framebuf4 framebuf8,...
  framebuf_subclass mpy_invalid namedtuple_asdict non_compliant resource_stream schedule,...
  sys_getsizeof urandom_extra ure_groups ure_span ure_sub ure_sub_unmatched vfs_basic,...
  vfs_fat_fileio1 vfs_fat_fileio2 vfs_fat_more vfs_fat_oldproto vfs_fat_ramdisk vfs,...
  userfs
```

### 1.8.18 Debugging

The easiest way to debug CircuitPython on hardware is with a JLink device, JLinkGDBServer, and an appropriate GDB. Instructions can be found at https://learn.adafruit.com/debugging-the-samd21-with-gdb

If using JLink, you'll need both the JLinkGDBServer and arm-none-eabi-gdb running.

Example:

```
JLinkGDBServer -if SWD -device ATSAMD51J19
arm-none-eabi-gdb build-metro_m4_express/firmware.elf -iex "target extended-remote :2331"
```

If your port/build includes arm-none-eabi-gdb-py, consider using it instead, as it can be used for better register debugging with https://github.com/bnahill/PyCortexMDebug

### 1.8.19 Code Quality Checks

We apply code quality checks using pre-commit. Install pre-commit once per system with

```
python3 -mpip install pre-commit
```

Activate it once per git clone with

```
pre-commit install
```

Pre-commit also requires some additional programs to be installed through your package manager:

- Standard Unix tools such as make, find, etc
- The gettext package, any modern version
- uncrustify version 0.71 (0.72 is also tested)

Each time you create a git commit, the pre-commit quality checks will be run. You can also run them e.g., with `pre-commit run foo.c` or `pre-commit run --all` to run on all files whether modified or not.

Some pre-commit quality checks require your active attention to resolve, others (such as the formatting checks of uncrustify) are made automatically and must simply be incorporated into your code changes by committing them.
1.8.20 Adafruit Community Code of Conduct

Our Pledge

In the interest of fostering an open and welcoming environment, we as contributors and leaders pledge to making participation in our project and our community a harassment-free experience for everyone, regardless of age, body size, disability, ethnicity, gender identity and expression, level or type of experience, education, socio-economic status, nationality, personal appearance, race, religion, or sexual identity and orientation.

Our Standards

We are committed to providing a friendly, safe and welcoming environment for all.

Examples of behavior that contributes to creating a positive environment include:

- Be kind and courteous to others
- Using welcoming and inclusive language
- Being respectful of differing viewpoints and experiences
- Collaborating with other community members
- Gracefully accepting constructive criticism
- Focusing on what is best for the community
- Showing empathy towards other community members

Examples of unacceptable behavior by participants include:

- The use of sexualized language or imagery and sexual attention or advances
- The use of inappropriate images, including in a community member’s avatar
- The use of inappropriate language, including in a community member’s nickname
- Any spamming, flaming, baiting or other attention-stealing behavior
- Excessive or unwelcome helping; answering outside the scope of the question asked
- Trolling, insulting/derogatory comments, and personal or political attacks
- Promoting or spreading disinformation, lies, or conspiracy theories against a person, group, organisation, project, or community
- Public or private harassment
- Publishing others’ private information, such as a physical or electronic address, without explicit permission
- Other conduct which could reasonably be considered inappropriate

The goal of the standards and moderation guidelines outlined here is to build and maintain a respectful community. We ask that you don’t just aim to be “technically unimpeachable”, but rather try to be your best self.

We value many things beyond technical expertise, including collaboration and supporting others within our community. Providing a positive experience for other community members can have a much more significant impact than simply providing the correct answer.
Our Responsibilities

Project leaders are responsible for clarifying the standards of acceptable behavior and are expected to take appropriate and fair corrective action in response to any instances of unacceptable behavior.

Project leaders have the right and responsibility to remove, edit, or reject messages, comments, commits, code, issues, and other contributions that are not aligned to this Code of Conduct, or to ban temporarily or permanently any community member for other behaviors that they deem inappropriate, threatening, offensive, or harmful.

Moderation

Instances of behaviors that violate the Adafruit Community Code of Conduct may be reported by any member of the community. Community members are encouraged to report these situations, including situations they witness involving other community members.

You may report in the following ways:

In any situation, you may send an email to support@adafruit.com.

On the Adafruit Discord, you may send an open message from any channel to all Community Moderators by tagging @community moderators. You may also send an open message from any channel, or a direct message to @kattni#1507, @tannewt#4653, @danh#1614, @cater#2442, @sommersoft#0222, @Mr. Certainly#0472 or @Andon#8175.

Email and direct message reports will be kept confidential.

In situations on Discord where the issue is particularly egregious, possibly illegal, requires immediate action, or violates the Discord terms of service, you should also report the message directly to Discord.

These are the steps for upholding our community’s standards of conduct.

1. Any member of the community may report any situation that violates the Adafruit Community Code of Conduct. All reports will be reviewed and investigated.

2. If the behavior is an egregious violation, the community member who committed the violation may be banned immediately, without warning.

3. Otherwise, moderators will first respond to such behavior with a warning.

4. Moderators follow a soft “three strikes” policy - the community member may be given another chance, if they are receptive to the warning and change their behavior.

5. If the community member is un receptive or unreasonable when warned by a moderator, or the warning goes unheeded, they may be banned for a first or second offense. Repeated offenses will result in the community member being banned.

Scope

This Code of Conduct and the enforcement policies listed above apply to all Adafruit Community venues. This includes but is not limited to any community spaces (both public and private), the entire Adafruit Discord server, and Adafruit GitHub repositories. Examples of Adafruit Community spaces include but are not limited to meet-ups, audio chats on the Adafruit Discord, or interaction at a conference.

This Code of Conduct applies both within project spaces and in public spaces when an individual is representing the project or its community. As a community member, you are representing our community, and are expected to behave accordingly.
Attribution


For other projects adopting the Adafruit Community Code of Conduct, please contact the maintainers of those projects for enforcement. If you wish to use this code of conduct for your own project, consider explicitly mentioning your moderation policy or making a copy with your own moderation policy so as to avoid confusion.

1.8.21 MicroPython & CircuitPython License

MIT License

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1.8.22 WebUSB Serial Support

To date, this has only been tested on one port (espressif), on one board (espressif_kaluga_1).

What it does

If you have ever used CircuitPython on a platform with a graphical LCD display, you have probably already seen multiple “consoles” in use (although the LCD console is “output only”).

New compile-time option CIRCUITPY_USB_VENDOR enables an additional “console” that can be used in parallel with the original (CDC) serial console.

Web pages that support the WebUSB standard can connect to the “vendor” interface and activate this WebUSB serial console at any time.

You can type into either console, and CircuitPython output is sent to all active consoles.

One example of a web page you can use to test drive this feature can be found at:

https://adafruit.github.io/Adafruit_TinyUSB_Arduino/examples/webusb-serial/index.html
**How to enable**

Update your platform’s mpconfigboard.mk file to enable and disable specific types of USB interfaces.

\[
\text{CIRCUITPY_USB_HID} = \text{xxx} \quad \text{CIRCUITPY_USB_MIDI} = \text{xxx} \quad \text{CIRCUITPY_USB_VENDOR} = \text{xxx}
\]

On at least some of the hardware platforms, the maximum number of USB endpoints is fixed. For example, on the ESP32S2, you must pick only one of the above 3 interfaces to be enabled.

Original espressif_kaluga_1 mpconfigboard.mk settings:

\[
\text{CIRCUITPY_USB_HID} = 1 \quad \text{CIRCUITPY_USB_MIDI} = 0 \quad \text{CIRCUITPY_USB_VENDOR} = 0
\]

Settings to enable WebUSB instead:

\[
\text{CIRCUITPY_USB_HID} = 0 \quad \text{CIRCUITPY_USB_MIDI} = 0 \quad \text{CIRCUITPY_USB_VENDOR} = 1
\]

Notice that to enable VENDOR on ESP32-S2, we had to give up HID. There may be platforms that can have both, or even all three.

**Implementation Notes**

CircuitPython uses the tinyusb library.

The tinyusb library already has support for WebUSB serial. The tinyusb examples already include a “WebUSB serial” example.

Sidenote - The use of the term "vendor" instead of "WebUSB" was done to match tinyusb.

Basically, this feature was ported into CircuitPython by pulling code snippets out of the tinyusb example, and putting them where they best belonged in the CircuitPython codebase.

**TODO: This needs to be reworked for dynamic USB descriptors.**
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