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# **python-can**

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## Contents

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<b>1</b>	<b>Installation</b>	<b>3</b>
1.1	GNU/Linux dependencies . . . . .	3
1.2	Windows dependencies . . . . .	3
1.3	Installing python-can in development mode . . . . .	4
<b>2</b>	<b>Configuration</b>	<b>5</b>
2.1	In Code . . . . .	5
2.2	Configuration File . . . . .	5
2.3	Environment Variables . . . . .	6
2.4	Interface Names . . . . .	6
<b>3</b>	<b>Library API</b>	<b>9</b>
3.1	Bus . . . . .	9
3.2	Thread safe bus . . . . .	12
3.3	Message . . . . .	13
3.4	Listeners . . . . .	16
3.5	Asycio support . . . . .	24
3.6	Broadcast Manager . . . . .	25
3.7	Internal API . . . . .	30
3.8	Utilities . . . . .	36
3.9	Notifier . . . . .	36
3.10	Errors . . . . .	37
<b>4</b>	<b>CAN Interface Modules</b>	<b>39</b>
4.1	SocketCAN . . . . .	39
4.2	Kvaser's CANLIB . . . . .	44
4.3	CAN over Serial . . . . .	46
4.4	CAN over Serial / SLCAN . . . . .	48
4.5	IXXAT Virtual CAN Interface . . . . .	49
4.6	PCAN Basic API . . . . .	50
4.7	USB2CAN Interface . . . . .	52
4.8	NI-CAN . . . . .	55
4.9	isCAN . . . . .	56
4.10	NEOVI Interface . . . . .	57
4.11	Vector . . . . .	58
4.12	Virtual . . . . .	60
4.13	CANalyst-II . . . . .	60

4.14	SYSTEC interface . . . . .	61
<b>5</b>	<b>Scripts</b>	<b>65</b>
5.1	can.logger . . . . .	65
5.2	can.player . . . . .	66
5.3	can.viewer . . . . .	67
<b>6</b>	<b>Developer's Overview</b>	<b>71</b>
6.1	Contributing . . . . .	71
6.2	Building & Installing . . . . .	71
6.3	Creating a new interface/backend . . . . .	71
6.4	Code Structure . . . . .	72
6.5	Creating a new Release . . . . .	72
<b>7</b>	<b>History and Roadmap</b>	<b>73</b>
7.1	Background . . . . .	73
7.2	Acknowledgements . . . . .	73
7.3	Support for CAN within Python . . . . .	74
<b>8</b>	<b>Known Bugs</b>	<b>75</b>
	<b>Python Module Index</b>	<b>77</b>

The **python-can** library provides Controller Area Network support for [Python](#), providing common abstractions to different hardware devices, and a suite of utilities for sending and receiving messages on a CAN bus.

**python-can** runs any where Python runs; from high powered computers with commercial *CAN to usb* devices right down to low powered devices running linux such as a BeagleBone or RaspberryPi.

More concretely, some example uses of the library:

- Passively logging what occurs on a CAN bus. For example monitoring a commercial vehicle using its **OBD-II** port.
- Testing of hardware that interacts via CAN. Modules found in modern cars, motorcycles, boats, and even wheelchairs have had components tested from Python using this library.
- Prototyping new hardware modules or software algorithms in-the-loop. Easily interact with an existing bus.
- Creating virtual modules to prototype CAN bus communication.

Brief example of the library in action: connecting to a CAN bus, creating and sending a message:

```

1  #!/usr/bin/env python
2  # coding: utf-8
3
4  """
5  This example shows how sending a single message works.
6  """
7
8  from __future__ import print_function
9
10 import can
11
12 def send_one():
13
14     # this uses the default configuration (for example from the config file)
15     # see http://python-can.readthedocs.io/en/latest/configuration.html
16     bus = can.interface.Bus()
17
18     # Using specific buses works similar:
19     # bus = can.interface.Bus(bustype='socketcan', channel='vcan0', bitrate=250000)
20     # bus = can.interface.Bus(bustype='pcan', channel='PCAN_USBBUS1', bitrate=250000)
21     # bus = can.interface.Bus(bustype='ixxat', channel=0, bitrate=250000)
22     # bus = can.interface.Bus(bustype='vector', app_name='CANalyzer', channel=0,
23     ↪bitrate=250000)
24     # ...
25
26     msg = can.Message(arbitration_id=0xc0ffee,
27                       data=[0, 25, 0, 1, 3, 1, 4, 1],
28                       is_extended_id=True)
29
30     try:
31         bus.send(msg)
32         print("Message sent on {}".format(bus.channel_info))
33     except can.CanError:
34         print("Message NOT sent")
35
36 if __name__ == '__main__':
37     send_one()

```

Contents:



Install `can` with `pip`:

```
$ pip install python-can
```

As most likely you will want to interface with some hardware, you may also have to install platform dependencies. Be sure to check any other specifics for your hardware in *[CAN Interface Modules](#)*.

## 1.1 GNU/Linux dependencies

Reasonably modern Linux Kernels (2.6.25 or newer) have an implementation of `socketcan`. This version of `python-can` will directly use `socketcan` if called with Python 3.3 or greater, otherwise that interface is used via `ctypes`.

## 1.2 Windows dependencies

### 1.2.1 Kvaser

To install `python-can` using the Kvaser CANLib SDK as the backend:

1. Install the [latest stable release](#) of Python.
2. Install Kvaser's [latest Windows CANLib drivers](#).
3. Test that Kvaser's own tools work to ensure the driver is properly installed and that the hardware is working.

### 1.2.2 PCAN

Download and install the latest driver for your interface from [PEAK-System's download page](#).

Note that PCANBasic API timestamps count seconds from system startup. To convert these to epoch times, the uptime library is used. If it is not available, the times are returned as number of seconds from system startup. To install the uptime library, run `pip install uptime`.

This library can take advantage of the [Python for Windows Extensions](#) library if installed. It will be used to get notified of new messages instead of the CPU intensive polling that will otherwise have be used.

### 1.2.3 IXXAT

To install `python-can` using the IXXAT VCI V3 SDK as the backend:

1. Install IXXAT's latest [Windows VCI V3 SDK drivers](#).
2. Test that IXXAT's own tools (i.e. MiniMon) work to ensure the driver is properly installed and that the hardware is working.

### 1.2.4 NI-CAN

Download and install the NI-CAN drivers from [National Instruments](#).

Currently the driver only supports 32-bit Python on Windows.

### 1.2.5 neoVI

See *NEOVI Interface*.

## 1.3 Installing python-can in development mode

A “development” install of this package allows you to make changes locally or pull updates from the Mercurial repository and use them without having to reinstall. Download or clone the source repository then:

```
python setup.py develop
```



Usually this library is used with a particular CAN interface, this can be specified in code, read from configuration files or environment variables.

See `can.util.load_config()` for implementation.

## 2.1 In Code

The `can` object exposes an `rc` dictionary which can be used to set the **interface** and **channel** before importing from `can.interfaces`.

```
import can
can.rc['interface'] = 'socketcan'
can.rc['channel'] = 'vcan0'
can.rc['bitrate'] = 500000
from can.interfaces.interface import Bus

bus = Bus()
```

You can also specify the interface and channel for each `Bus` instance:

```
import can

bus = can.interface.Bus(bustype='socketcan', channel='vcan0', bitrate=500000)
```

## 2.2 Configuration File

On Linux systems the config file is searched in the following paths:

1. `~/can.conf`
2. `/etc/can.conf`

3. \$HOME/.can
4. \$HOME/.canrc

On Windows systems the config file is searched in the following paths:

1. ~/can.conf
2. can.ini (current working directory)
3. \$APPDATA/can.ini

The configuration file sets the default interface and channel:

```
[default]
interface = <the name of the interface to use>
channel = <the channel to use by default>
bitrate = <the bitrate in bits/s to use by default>
```

The configuration can also contain additional sections (or context):

```
[default]
interface = <the name of the interface to use>
channel = <the channel to use by default>
bitrate = <the bitrate in bits/s to use by default>

[HS]
# All the values from the 'default' section are inherited
channel = <the channel to use>
bitrate = <the bitrate in bits/s to use. i.e. 500000>

[MS]
# All the values from the 'default' section are inherited
channel = <the channel to use>
bitrate = <the bitrate in bits/s to use. i.e. 125000>
```

```
from can.interfaces.interface import Bus

hs_bus = Bus(context='HS')
ms_bus = Bus(context='MS')
```

## 2.3 Environment Variables

Configuration can be pulled from these environmental variables:

- CAN\_INTERFACE
- CAN\_CHANNEL
- CAN\_BITRATE

## 2.4 Interface Names

Lookup table of interface names:

Name	Documentation
"socketcan"	<i>SocketCAN</i>
"kvaser"	<i>Kvaser's CANLIB</i>
"serial"	<i>CAN over Serial</i>
"slcan"	<i>CAN over Serial / SLCAN</i>
"ixxat"	<i>IXXAT Virtual CAN Interface</i>
"pcan"	<i>PCAN Basic API</i>
"usb2can"	<i>USB2CAN Interface</i>
"nican"	<i>NI-CAN</i>
"iscan"	<i>isCAN</i>
"neovi"	<i>NEOVI Interface</i>
"vector"	<i>Vector</i>
"virtual"	<i>Virtual</i>



The main objects are the *BusABC* and the *Message*. A form of CAN interface is also required.

**Hint:** Check the backend specific documentation for any implementation specific details.

## 3.1 Bus

The *BusABC* class, as the name suggests, provides an abstraction of a CAN bus. The bus provides a wrapper around a physical or virtual CAN Bus. An interface specific instance of the *BusABC* is created by the *Bus* class, for example:

```
vector_bus = can.Bus(interface='vector', ...)
```

That bus is then able to handle the interface specific software/hardware interactions and implements the *BusABC* API. A thread safe bus wrapper is also available, see *Thread safe bus*.

### 3.1.1 Autoconfig Bus

**class** `can.Bus` (*channel*, *can\_filters=None*, *\*\*config*)

Bases: `can.bus.BusABC`

Bus wrapper with configuration loading.

Instantiates a CAN Bus of the given *interface*, falls back to reading a configuration file from default locations.

Construct and open a CAN bus instance of the specified type.

Subclasses should call though this method with all given parameters as it handles generic tasks like applying filters.

#### Parameters

- **channel** – The can interface identifier. Expected type is backend dependent.
- **can\_filters** (*list*) – See `set_filters()` for details.
- **config** (*dict*) – Any backend dependent configurations are passed in this dictionary

### 3.1.2 API

**class** `can.BusABC` (*channel*, *can\_filters=None*, *\*\*config*)

Bases: `object`

The CAN Bus Abstract Base Class that serves as the basis for all concrete interfaces.

This class may be used as an iterator over the received messages.

Construct and open a CAN bus instance of the specified type.

Subclasses should call though this method with all given parameters as it handles generic tasks like applying filters.

#### Parameters

- **channel** – The can interface identifier. Expected type is backend dependent.
- **can\_filters** (*list*) – See `set_filters()` for details.
- **config** (*dict*) – Any backend dependent configurations are passed in this dictionary

**\_\_iter\_\_** ()

Allow iteration on messages as they are received.

```
>>> for msg in bus:
...     print(msg)
```

Yields `can.Message` msg objects.

**RECV\_LOGGING\_LEVEL** = 9

Log level for received messages

**channel\_info** = 'unknown'

a string describing the underlying bus and/or channel

**filters**

Modify the filters of this bus. See `set_filters()` for details.

**flush\_tx\_buffer** ()

Discard every message that may be queued in the output buffer(s).

**recv** (*timeout=None*)

Block waiting for a message from the Bus.

**Parameters** **timeout** (*float or None*) – seconds to wait for a message or None to wait indefinitely

**Return type** `can.Message` or `None`

**Returns** None on timeout or a `can.Message` object.

**Raises** `can.CanError` – if an error occurred while reading

**send** (*msg*, *timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (*can.Message*) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** *can.CanError* – if the message could not be sent

**send\_periodic** (*msg*, *period*, *duration=None*, *store\_task=True*)

Start sending a message at a given period on this bus.

The task will be active until one of the following conditions are met:

- the (optional) duration expires
- the Bus instance goes out of scope
- the Bus instance is shutdown
- *BusABC.stop\_all\_periodic\_tasks()* is called
- the task's *CyclicTask.stop()* method is called.

#### Parameters

- **msg** (*can.Message*) – Message to transmit
- **period** (*float*) – Period in seconds between each message
- **duration** (*float*) – The duration to keep sending this message at given rate. If no duration is provided, the task will continue indefinitely.
- **store\_task** (*bool*) – If True (the default) the task will be attached to this Bus instance. Disable to instead manage tasks manually.

**Returns** A started task instance. Note the task can be stopped (and depending on the backend modified) by calling the *stop()* method.

**Return type** *can.broadcastmanager.CyclicSendTaskABC*

---

**Note:** Note the duration before the message stops being sent may not be exactly the same as the duration specified by the user. In general the message will be sent at the given rate until at least **duration** seconds.

---



---

**Note:** For extremely long running Bus instances with many short lived tasks the default api with *store\_task==True* may not be appropriate as the stopped tasks are still taking up memory as they are associated with the Bus instance.

---

**set\_filters** (*filters=None*)

Apply filtering to all messages received by this Bus.

All messages that match at least one filter are returned. If *filters* is *None* or a zero length sequence, all messages are matched.

Calling without passing any filters will reset the applied filters to *None*.

**Parameters** **filters** – A iterable of dictionaries each containing a “can\_id”, a “can\_mask”, and an optional “extended” key.

```
>>> [{"can_id": 0x11, "can_mask": 0x21, "extended": False}]
```

A filter matches, when `<received_can_id> & can_mask == can_id & can_mask`. If `extended` is set as well, it only matches messages where `<received_is_extended> == extended`. Else it matches every messages based only on the arbitration ID and mask.

**shutdown()**

Called to carry out any interface specific cleanup required in shutting down a bus.

**state**

Return the current state of the hardware

**Returns** ACTIVE, PASSIVE or ERROR

**Return type** NamedTuple

**stop\_all\_periodic\_tasks** (*remove\_tasks=True*)

Stop sending any messages that were started using `bus.send_periodic`

**Parameters** **remove\_tasks** (*bool*) – Stop tracking the stopped tasks.

### 3.1.3 Transmitting

Writing individual messages to the bus is done by calling the `send()` method and passing a *Message* instance. Periodic sending is controlled by the *broadcast manager*.

### 3.1.4 Receiving

Reading from the bus is achieved by either calling the `recv()` method or by directly iterating over the bus:

```
for msg in bus:
    print(msg.data)
```

Alternatively the *Listener* api can be used, which is a list of *Listener* subclasses that receive notifications when new messages arrive.

### 3.1.5 Filtering

Message filtering can be set up for each bus. Where the interface supports it, this is carried out in the hardware or kernel layer - not in Python.

## 3.2 Thread safe bus

This thread safe version of the *BusABC* class can be used by multiple threads at once. Sending and receiving is locked separately to avoid unnecessary delays. Conflicting calls are executed by blocking until the bus is accessible.

It can be used exactly like the normal *BusABC*:



```
# 'socketcan' is only an example interface, it works with all the others too
my_bus = can.ThreadSafeBus(interface='socketcan', channel='vcan0')
my_bus.send(...) my_bus.recv(...)
```

```
class can.ThreadSafeBus(*args, **kwargs)
```

Bases: `ObjectProxy`

Contains a thread safe `can.BusABC` implementation that wraps around an existing interface instance. All public methods of that base class are now safe to be called from multiple threads. The send and receive methods are synchronized separately.

Use this as a drop-in replacement for `BusABC`.

---

**Note:** This approach assumes that both `send()` and `_recv_internal()` of the underlying bus instance can be called simultaneously, and that the methods use `_recv_internal()` instead of `recv()` directly.

---

### 3.3 Message

```
class can.Message(timestamp=0.0, arbitration_id=0, is_extended_id=None, is_remote_frame=False,
                  is_error_frame=False, channel=None, dlc=None, data=None, is_fd=False,
                  bitrate_switch=False, error_state_indicator=False, extended_id=None,
                  check=False)
```

Bases: `object`

The `Message` object is used to represent CAN messages for sending, receiving and other purposes like converting between different logging formats.

Messages can use extended identifiers, be remote or error frames, contain data and may be associated to a channel.

Messages are always compared by identity and never by value, because that may introduce unexpected behaviour. See also `equals()`.

`copy()/deepcopy()` is supported as well.

Messages do not support “dynamic” attributes, meaning any others that the documented ones.

To create a message object, simply provide any of the below attributes together with additional parameters as keyword arguments to the constructor.

**Parameters** `check` (*bool*) – By default, the constructor of this class does not strictly check the input. Thus, the caller must prevent the creation of invalid messages or set this parameter to `True`, to raise an `Error` on invalid inputs. Possible problems include the `dlc` field not matching the length of `data` or creating a message with both `is_remote_frame` and `is_error_frame` set to `True`.

**Raises** `ValueError` – iff `check` is set to `True` and one or more arguments were invalid

One can instantiate a `Message` defining data, and optional arguments for all attributes such as arbitration ID, flags, and timestamp.

```
>>> from can import Message
>>> test = Message(data=[1, 2, 3, 4, 5])
>>> test.data
bytearray(b'\x01\x02\x03\x04\x05')
>>> test.dlc
5
```

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```
>>> print(test)
Timestamp:      0.000000      ID: 00000000      010      DLC: 5      01 02 03 04 05
```

The `arbitration_id` field in a CAN message may be either 11 bits (standard addressing, CAN 2.0A) or 29 bits (extended addressing, CAN 2.0B) in length, and `python-can` exposes this difference with the `is_extended_id` attribute.

#### timestamp

Type `float`

The timestamp field in a CAN message is a floating point number representing when the message was received since the epoch in seconds. Where possible this will be timestamped in hardware.

#### arbitration\_id

Type `int`

The frame identifier used for arbitration on the bus.

The arbitration ID can take an int between 0 and the maximum value allowed depending on the `is_extended_id` flag (either  $2^{11} - 1$  for 11-bit IDs, or  $2^{29} - 1$  for 29-bit identifiers).

```
>>> print(Message(is_extended_id=False, arbitration_id=100))
Timestamp:      0.000000      ID: 0064      S      DLC: 0
```

#### data

Type `bytearray`

The data parameter of a CAN message is exposed as a **bytearray** with length between 0 and 8.

```
>>> example_data = bytearray([1, 2, 3])
>>> print(Message(data=example_data))
Timestamp:      0.000000      ID: 00000000      X      DLC: 3      01 02 03
```

A `Message` can also be created with bytes, or lists of ints:

```
>>> m1 = Message(data=[0x64, 0x65, 0x61, 0x64, 0x62, 0x65, 0x65, 0x66])
>>> print(m1.data)
bytearray(b'deadbeef')
>>> m2 = Message(data=b'deadbeef')
>>> m2.data
bytearray(b'deadbeef')
```

#### dlc

Type `int`

The DLC (Data Length Code) parameter of a CAN message is an integer between 0 and 8 representing the frame payload length.

In the case of a CAN FD message, this indicates the data length in number of bytes.

```
>>> m = Message(data=[1, 2, 3])
>>> m.dlc
3
```

**Note:** The DLC value does not necessarily define the number of bytes of data in a message.

Its purpose varies depending on the frame type - for data frames it represents the amount of data contained in the message, in remote frames it represents the amount of data being requested.

#### channel

Type `str` or `int` or `None`

This might store the channel from which the message came.

#### is\_extended\_id

Type `bool`

This flag controls the size of the `arbitration_id` field. Previously this was exposed as `id_type`.

```
>>> print(Message(is_extended_id=False))
Timestamp:      0.000000      ID: 0000      S      DLC: 0
>>> print(Message(is_extended_id=True))
Timestamp:      0.000000      ID: 00000000      X      DLC: 0
```

**Note:** The initializer argument and attribute `extended_id` has been deprecated in favor of `is_extended_id`, but will continue to work for the 3.x release series.

#### is\_error\_frame

Type `bool`

This boolean parameter indicates if the message is an error frame or not.

```
>>> print(Message(is_error_frame=True))
Timestamp:      0.000000      ID: 00000000      X E      DLC: 0
```

#### is\_remote\_frame

Type `bool`

This boolean attribute indicates if the message is a remote frame or a data frame, and modifies the bit in the CAN message's flags field indicating this.

```
>>> print(Message(is_remote_frame=True))
Timestamp:      0.000000      ID: 00000000      X R      DLC: 0
```

#### is\_fd

Type `bool`

Indicates that this message is a CAN FD message.

#### bitrate\_switch

Type `bool`

If this is a CAN FD message, this indicates that a higher bitrate was used for the data transmission.

#### error\_state\_indicator

Type `bool`

If this is a CAN FD message, this indicates an error active state.

#### \_\_str\_\_()

A string representation of a CAN message:

```

>>> from can import Message
>>> test = Message()
>>> print(test)
Timestamp:      0.000000      ID: 00000000      X      DLC: 0
>>> test2 = Message(data=[1, 2, 3, 4, 5])
>>> print(test2)
Timestamp:      0.000000      ID: 00000000      X      DLC: 5      01 02 03 04_
↪05

```

The fields in the printed message are (in order):

- timestamp,
- arbitration ID,
- flags,
- dlc,
- and data.

The flags field is represented as one, two or three letters:

- X if the `is_extended_id` attribute is set, otherwise S,
- E if the `is_error_frame` attribute is set,
- R if the `is_remote_frame` attribute is set.

The arbitration ID field is represented as either a four or eight digit hexadecimal number depending on the length of the arbitration ID (11-bit or 29-bit).

Each of the bytes in the data field (when present) are represented as two-digit hexadecimal numbers.

**equals** (*other*, *timestamp\_delta=1e-06*)

Compares a given message with this one.

#### Parameters

- **other** (`can.Message`) – the message to compare with
- **timestamp\_delta** (*float or int or None*) – the maximum difference at which two timestamps are still considered equal or None to not compare timestamps

**Return type** `bool`

**Returns** True iff the given message equals this one

## 3.4 Listeners

### 3.4.1 Listener

The Listener class is an “abstract” base class for any objects which wish to register to receive notifications of new messages on the bus. A Listener can be used in two ways; the default is to **call** the Listener with a new message, or by calling the method **on\_message\_received**.

Listeners are registered with *Notifier* object(s) which ensure they are notified whenever a new message is received.

Subclasses of Listener that do not override **on\_message\_received** will cause `NotImplementedError` to be thrown when a message is received on the CAN bus.

**class** `can.Listener`Bases: `object`

The basic listener that can be called directly to handle some CAN message:

```
listener = SomeListener()
msg = my_bus.recv()

# now either call
listener(msg)
# or
listener.on_message_received(msg)

# Important to ensure all outputs are flushed
listener.stop()
```

**on\_error** (*exc*)

This method is called to handle any exception in the receive thread.

**Parameters** *exc* (*Exception*) – The exception causing the thread to stop

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters** *msg* (`can.Message`) – the delivered message

**stop** ()

Stop handling new messages, carry out any final tasks to ensure data is persisted and cleanup any open resources.

Concrete implementations override.

There are some listeners that already ship together with *python-can* and are listed below. Some of them allow messages to be written to files, and the corresponding file readers are also documented here.

---

**Note:** Please note that writing and the reading a message might not always yield a completely unchanged message again, since some properties are not (yet) supported by some file formats.

---

### 3.4.2 BufferedReader

**class** `can.BufferedReader`Bases: `can.listener.Listener`

A `BufferedReader` is a subclass of `Listener` which implements a **message buffer**: that is, when the `can.BufferedReader` instance is notified of a new message it pushes it into a queue of messages waiting to be serviced. The messages can then be fetched with `get_message()`.

Putting in messages after `stop()` has been called will raise an exception, see `on_message_received()`.

**Attr** `bool is_stopped` True iff the reader has been stopped

**get\_message** (*timeout=0.5*)

Attempts to retrieve the latest message received by the instance. If no message is available it blocks for given timeout or until a message is received, or else returns None (whichever is shorter). This method does not block after `can.BufferedReader.stop()` has been called.

**Parameters** *timeout* (*float*) – The number of seconds to wait for a new message.

**Rtype** `can.Message` or None

**Returns** the message if there is one, or None if there is not.

**on\_message\_received** (*msg*)

Append a message to the buffer.

**Raises** `BufferError` if the reader has already been stopped

**stop** ()

Prohibits any more additions to this reader.

**class** `can.AsyncBufferedReader` (*loop=None*)

Bases: `can.listener.Listener`

A message buffer for use with `asyncio`.

See *Asyncio support* for how to use with `can.Notifier`.

Can also be used as an asynchronous iterator:

```
async for msg in reader:
    print(msg)
```

**get\_message** ()

Retrieve the latest message when awaited for:

```
msg = await reader.get_message()
```

**Return type** `can.Message`

**Returns** The CAN message.

**on\_message\_received** (*msg*)

Append a message to the buffer.

Must only be called inside an event loop!

### 3.4.3 Logger

The `can.Logger` uses the following `can.Listener` types to create log files with different file types of the messages received.

**class** `can.Logger` (*file, mode='rt'*)

Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

Logs CAN messages to a file.

The format is determined from the file format which can be one of:

- .asc: `can.ASCWriter`
- .blf `can.BLFWriter`
- .csv: `can.CSVWriter`
- .db: `can.SqliteWriter`
- .log `can.CanutilsLogWriter`
- other: `can.Printer`

The log files may be incomplete until `stop()` is called due to buffering.

---

**Note:** This class itself is just a dispatcher, and any positional and keyword arguments are passed on to the returned instance.

---

#### Parameters

- **file** – a path-like object to open a file, a file-like object to be used as a file or *None* to not use a file at all
- **mode** (*str*) – the mode that should be used to open the file, see `open()`, ignored if *file* is *None*

### 3.4.4 Printer

**class** `can.Printer` (*file=None*)

Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

The Printer class is a subclass of `Listener` which simply prints any messages it receives to the terminal (stdout). A message is turned into a string using `__str__()`.

**Attr bool write\_to\_file** *True* iff this instance prints to a file instead of standard out

**Parameters file** – an optional path-like object or as file-like object to “print” to instead of writing to standard out (stdout) If this is a file-like object, it has to be opened in text write mode, not binary write mode.

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters msg** (`can.Message`) – the delivered message

### 3.4.5 CSVWriter

**class** `can.CSVWriter` (*file*, *append=False*)

Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

Writes a comma separated text file with a line for each message. Includes a header line.

The columns are as follows:

name of column	format description	example
timestamp	decimal float	1483389946.197
arbitration_id	hex	0x00dadada
extended	1 == True, 0 == False	1
remote	1 == True, 0 == False	0
error	1 == True, 0 == False	0
dlc	int	6
data	base64 encoded	WzQyLCA5XQ==

Each line is terminated with a platform specific line separator.

#### Parameters

- **file** – a path-like object or a file-like object to write to. If this is a file-like object, it has to be opened in text write mode, not binary write mode.

- **append** (*bool*) – if set to *True* messages are appended to the file and no header line is written, else the file is truncated and starts with a newly written header line

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters** *msg* (*can.Message*) – the delivered message

**class** *can.CSVReader* (*file*)

Bases: *can.io.generic.BaseIOHandler*

Iterator over CAN messages from a .csv file that was generated by *CSVWriter* or that uses the same format as described there. Assumes that there is a header and thus skips the first line.

Any line separator is accepted.

**Parameters** *file* – a path-like object or as file-like object to read from If this is a file-like object, it has to be opened in text read mode, not binary read mode.

### 3.4.6 SqliteWriter

**class** *can.SqliteWriter* (*file*, *table\_name*='messages')

Bases: *can.io.generic.BaseIOHandler*, *can.listener.BufferedReader*

Logs received CAN data to a simple SQL database.

The sqlite database may already exist, otherwise it will be created when the first message arrives.

Messages are internally buffered and written to the SQL file in a background thread. Ensures that all messages that are added before calling *stop()* are actually written to the database after that call returns. Thus, calling *stop()* may take a while.

**Attr str table\_name** the name of the database table used for storing the messages

**Attr int num\_frames** the number of frames actually written to the database, this excludes messages that are still buffered

**Attr float last\_write** the last time a message was actually written to the database, as given by *time.time()*

---

**Note:** When the listener's *stop()* method is called the thread writing to the database will continue to receive and internally buffer messages if they continue to arrive before the *GET\_MESSAGE\_TIMEOUT*.

If the *GET\_MESSAGE\_TIMEOUT* expires before a message is received, the internal buffer is written out to the database file.

However if the bus is still saturated with messages, the Listener will continue receiving until the *MAX\_TIME\_BETWEEN\_WRITES* timeout is reached or more than *MAX\_BUFFER\_SIZE\_BEFORE\_WRITES* messages are buffered.

---

---

**Note:** The database schema is given in the documentation of the loggers.

---

#### Parameters

- **file** – a *str* or since Python 3.7 a path like object that points to the database file to use
- **table\_name** (*str*) – the name of the table to store messages in



**Warning:** In contrary to all other readers/writers the Sqlite handlers do not accept file-like objects as the *file* parameter.

**GET\_MESSAGE\_TIMEOUT = 0.25**

Number of seconds to wait for messages from internal queue

**MAX\_BUFFER\_SIZE\_BEFORE\_WRITES = 500**

Maximum number of messages to buffer before writing to the database

**MAX\_TIME\_BETWEEN\_WRITES = 5.0**

Maximum number of seconds to wait between writes to the database

**stop()**

Stops the reader and writes all remaining messages to the database. Thus, this might take a while and block.

**class** `can.SqliteReader` (*file*, *table\_name*='messages')

Bases: `can.io.generic.BaseIOHandler`

Reads recorded CAN messages from a simple SQL database.

This class can be iterated over or used to fetch all messages in the database with `read_all()`.

Calling `len()` on this object might not run in constant time.

**Attr str table\_name** the name of the database table used for storing the messages

---

**Note:** The database schema is given in the documentation of the loggers.

---

#### Parameters

- **file** – a *str* or since Python 3.7 a path like object that points to the database file to use
- **table\_name** (*str*) – the name of the table to look for the messages

**Warning:** In contrary to all other readers/writers the Sqlite handlers do not accept file-like objects as the *file* parameter. It also runs in `append=True` mode all the time.

**read\_all()**

Fetches all messages in the database.

**Return type** Generator[`can.Message`]

**stop()**

Closes the connection to the database.

#### Database table format

The messages are written to the table `messages` in the sqlite database by default. The table is created if it does not already exist.

The entries are as follows:

Name	Data type	Note
ts	REAL	The timestamp of the message
arbitration_id	INTEGER	The arbitration id, might use the extended format
extended	INTEGER	1 if the arbitration id uses the extended format, else 0
remote	INTEGER	1 if the message is a remote frame, else 0
error	INTEGER	1 if the message is an error frame, else 0
dlc	INTEGER	The data length code (DLC)
data	BLOB	The content of the message

### 3.4.7 ASC (.asc Logging format)

ASCWriter logs CAN data to an ASCII log file compatible with other CAN tools such as Vector CANalyzer/CANoe and other. Since no official specification exists for the format, it has been reverse-engineered from existing log files. One description of the format can be found [here](#).

---

**Note:** Channels will be converted to integers.

---

**class** `can.ASCWriter` (*file*, *channel=1*)

Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

Logs CAN data to an ASCII log file (.asc).

The measurement starts with the timestamp of the first registered message. If a message has a timestamp smaller than the previous one or None, it gets assigned the timestamp that was written for the last message. If the first message does not have a timestamp, it is set to zero.

#### Parameters

- **file** – a path-like object or as file-like object to write to. If this is a file-like object, it has to be opened in text write mode, not binary write mode.
- **channel** – a default channel to use when the message does not have a channel set

**log\_event** (*message*, *timestamp=None*)

Add a message to the log file.

#### Parameters

- **message** (*str*) – an arbitrary message
- **timestamp** (*float*) – the absolute timestamp of the event

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters** **msg** (`can.Message`) – the delivered message

**stop** ()

Stop handling new messages, carry out any final tasks to ensure data is persisted and cleanup any open resources.

Concrete implementations override.

ASCReader reads CAN data from ASCII log files .asc, as further references can-util can be used: `asc2log`, `log2asc`.

**class** `can.ASCReader` (*file*)

Bases: `can.io.generic.BaseIOHandler`

Iterator of CAN messages from a ASC logging file.

TODO: turn relative timestamps back to absolute form

**Parameters** **file** – a path-like object or as file-like object to read from If this is a file-like object, is has to opened in text read mode, not binary read mode.

### 3.4.8 Log (.log can-utils Logging format)

CanutilsLogWriter logs CAN data to an ASCII log file compatible with *can-utils* <<https://github.com/linux-can/can-utils>> As specification following references can-utils can be used: [asc2log](#), [log2asc](#).

**class** `can.CanutilsLogWriter` (*file*, *channel*=`'vcan0'`, *append*=`False`)  
 Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

Logs CAN data to an ASCII log file (.log). This class is is compatible with “candump -L”.

If a message has a timestamp smaller than the previous one (or 0 or None), it gets assigned the timestamp that was written for the last message. If the first message does not have a timestamp, it is set to zero.

#### Parameters

- **file** – a path-like object or as file-like object to write to If this is a file-like object, is has to opened in text write mode, not binary write mode.
- **channel** – a default channel to use when the message does not have a channel set
- **append** (*bool*) – if set to `True` messages are appended to the file, else the file is truncated

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters** **msg** (`can.Message`) – the delivered message

**CanutilsLogReader** reads CAN data from ASCII log files .log

**class** `can.CanutilsLogReader` (*file*)  
 Bases: `can.io.generic.BaseIOHandler`

Iterator over CAN messages from a .log Logging File (candump -L).

---

**Note:** .log-format looks for example like this:

```
(0.0) vcan0 001#8d00100100820100
```

---

**Parameters** **file** – a path-like object or as file-like object to read from If this is a file-like object, is has to opened in text read mode, not binary read mode.

### 3.4.9 BLF (Binary Logging Format)

Implements support for BLF (Binary Logging Format) which is a proprietary CAN log format from Vector Informatik GmbH.

The data is stored in a compressed format which makes it very compact.

---

**Note:** Channels will be converted to integers.

---

**class** `can.BLFWriter` (*file*, *channel=1*)

Bases: `can.io.generic.BaseIOHandler`, `can.listener.Listener`

Logs CAN data to a Binary Logging File compatible with Vector's tools.

**Parameters** **file** – a path-like object or as file-like object to write to If this is a file-like object, is has to opened in binary write mode, not text write mode.

**COMPRESSION\_LEVEL** = 9

ZLIB compression level

**MAX\_CACHE\_SIZE** = 131072

Max log container size of uncompressed data

**log\_event** (*text*, *timestamp=None*)

Add an arbitrary message to the log file as a global marker.

**Parameters**

- **text** (*str*) – The group name of the marker.
- **timestamp** (*float*) – Absolute timestamp in Unix timestamp format. If not given, the marker will be placed along the last message.

**on\_message\_received** (*msg*)

This method is called to handle the given message.

**Parameters** **msg** (`can.Message`) – the delivered message

**stop** ()

Stops logging and closes the file.

The following class can be used to read messages from BLF file:

**class** `can.BLFReader` (*file*)

Bases: `can.io.generic.BaseIOHandler`

Iterator of CAN messages from a Binary Logging File.

Only CAN messages and error frames are supported. Other object types are silently ignored.

**Parameters** **file** – a path-like object or as file-like object to read from If this is a file-like object, is has to opened in binary read mode, not text read mode.

## 3.5 Asyncio support

The `asyncio` module built into Python 3.4 and later can be used to write asynchronous code in a single thread. This library supports receiving messages asynchronously in an event loop using the `can.Notifier` class.

There will still be one thread per CAN bus but the user application will execute entirely in the event loop, allowing simpler concurrency without worrying about threading issues. Interfaces that have a valid file descriptor will however be supported natively without a thread.

You can also use the `can.AsyncBufferedReader` listener if you prefer to write coroutine based code instead of using callbacks.

### 3.5.1 Example

Here is an example using both callback and coroutine based code:

```

import asyncio
import can

def print_message(msg):
    """Regular callback function. Can also be a coroutine."""
    print(msg)

async def main():
    can0 = can.Bus('vcan0', bustype='virtual', receive_own_messages=True)
    reader = can.AsyncBufferedReader()
    logger = can.Logger('logfile.asc')

    listeners = [
        print_message,  # Callback function
        reader,         # AsyncBufferedReader() listener
        logger,          # Regular Listener object
    ]
    # Create Notifier with an explicit loop to use for scheduling of callbacks
    loop = asyncio.get_event_loop()
    notifier = can.Notifier(can0, listeners, loop=loop)
    # Start sending first message
    can0.send(can.Message(arbitration_id=0))

    print('Bouncing 10 messages...')
    for _ in range(10):
        # Wait for next message from AsyncBufferedReader
        msg = await reader.get_message()
        # Delay response
        await asyncio.sleep(0.5)
        msg.arbitration_id += 1
        can0.send(msg)
    # Wait for last message to arrive
    await reader.get_message()
    print('Done!')

    # Clean-up
    notifier.stop()
    can0.shutdown()

# Get the default event loop
loop = asyncio.get_event_loop()
# Run until main coroutine finishes
loop.run_until_complete(main())
loop.close()

```

## 3.6 Broadcast Manager

The broadcast manager allows the user to setup periodic message jobs. For example sending a particular message at a given period. The broadcast manager supported natively by several interfaces and a software thread based scheduler is used as a fallback.

This example shows the socketcan backend using the broadcast manager:

```

1 #!/usr/bin/env python
2 # coding: utf-8

```

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```

3
4 """
5 This example exercises the periodic sending capabilities.
6
7 Expects a vcan0 interface:
8
9     python3 -m examples.cyclic
10
11 """
12
13 from __future__ import print_function
14
15 import logging
16 import time
17
18 import can
19
20 logging.basicConfig(level=logging.INFO)
21
22
23 def simple_periodic_send(bus):
24     """
25     Sends a message every 20ms with no explicit timeout
26     Sleeps for 2 seconds then stops the task.
27     """
28     print("Starting to send a message every 200ms for 2s")
29     msg = can.Message(arbitration_id=0x123, data=[1, 2, 3, 4, 5, 6], is_extended_
↪ id=False)
30     task = bus.send_periodic(msg, 0.20)
31     assert isinstance(task, can.CyclicSendTaskABC)
32     time.sleep(2)
33     task.stop()
34     print("stopped cyclic send")
35
36
37 def limited_periodic_send(bus):
38     print("Starting to send a message every 200ms for 1s")
39     msg = can.Message(arbitration_id=0x12345678, data=[0, 0, 0, 0, 0, 0], is_extended_
↪ id=True)
40     task = bus.send_periodic(msg, 0.20, 1, store_task=False)
41     if not isinstance(task, can.LimitedDurationCyclicSendTaskABC):
42         print("This interface doesn't seem to support a ")
43         task.stop()
44         return
45
46     time.sleep(2)
47     print("Cyclic send should have stopped as duration expired")
48     # Note the (finished) task will still be tracked by the Bus
49     # unless we pass `store_task=False` to bus.send_periodic
50     # alternatively calling stop removes the task from the bus
51     #task.stop()
52
53
54 def test_periodic_send_with_modifying_data(bus):
55     print("Starting to send a message every 200ms. Initial data is ones")
56     msg = can.Message(arbitration_id=0x0cf02200, data=[1, 1, 1, 1])
57     task = bus.send_periodic(msg, 0.20)

```

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```

58     if not isinstance(task, can.ModifiableCyclicTaskABC):
59         print("This interface doesn't seem to support modification")
60         task.stop()
61         return
62     time.sleep(2)
63     print("Changing data of running task to begin with 99")
64     msg.data[0] = 0x99
65     task.modify_data(msg)
66     time.sleep(2)
67
68     task.stop()
69     print("stopped cyclic send")
70     print("Changing data of stopped task to single ff byte")
71     msg.data = bytearray([0xff])
72     msg.dlc = 1
73     task.modify_data(msg)
74     time.sleep(1)
75     print("starting again")
76     task.start()
77     time.sleep(1)
78     task.stop()
79     print("done")
80
81
82 # Will have to consider how to expose items like this. The socketcan
83 # interfaces will continue to support it... but the top level api won't.
84 # def test_dual_rate_periodic_send():
85 #     """Send a message 10 times at 1ms intervals, then continue to send every 500ms"""
86 #     ↪
87 #     msg = can.Message(arbitration_id=0x123, data=[0, 1, 2, 3, 4, 5])
88 #     print("Creating cyclic task to send message 10 times at 1ms, then every 500ms")
89 #     task = can.interface.MultiRateCyclicSendTask('vcan0', msg, 10, 0.001, 0.50)
90 #     time.sleep(2)
91 #
92 #     print("Changing data[0] = 0x42")
93 #     msg.data[0] = 0x42
94 #     task.modify_data(msg)
95 #     time.sleep(2)
96 #
97 #     task.stop()
98 #     print("stopped cyclic send")
99 #
100 #     time.sleep(2)
101 #
102 #     task.start()
103 #     print("starting again")
104 #     time.sleep(2)
105 #     task.stop()
106 #     print("done")
107
108 if __name__ == "__main__":
109
110     reset_msg = can.Message(arbitration_id=0x00, data=[0, 0, 0, 0, 0, 0], is_extended_
111     ↪id=False)
112
113     for interface, channel in [

```

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```

113         ('socketcan', 'vcan0'),
114         #('ixxat', 0)
115     ]:
116         print("Carrying out cyclic tests with {} interface".format(interface))
117
118         bus = can.Bus(interface=interface, channel=channel, bitrate=500000)
119         bus.send(reset_msg)
120
121         simple_periodic_send(bus)
122
123         bus.send(reset_msg)
124
125         limited_periodic_send(bus)
126
127         test_periodic_send_with_modifying_data(bus)
128
129         #print("Carrying out multirate cyclic test for {} interface".
↪format(interface))
130         #can.rc['interface'] = interface
131         #test_dual_rate_periodic_send()
132
133         bus.shutdown()
134
135     time.sleep(2)

```

### 3.6.1 Message Sending Tasks

The class based api for the broadcast manager uses a series of `mixin classes`. All mixins inherit from `CyclicSendTaskABC` which inherits from `CyclicTask`.

**class** `can.broadcastmanager.CyclicTask`

Bases: `object`

Abstract Base for all cyclic tasks.

**stop()**

Cancel this periodic task.

**Raises** `can.CanError` – If stop is called on an already stopped task.

**class** `can.broadcastmanager.CyclicSendTaskABC(message, period)`

Bases: `can.broadcastmanager.CyclicTask`

Message send task with defined period

**Parameters**

- **message** (`can.Message`) – The message to be sent periodically.
- **period** (`float`) – The rate in seconds at which to send the message.

**class** `can.broadcastmanager.LimitedDurationCyclicSendTaskABC(message, period, duration)`

Bases: `can.broadcastmanager.CyclicSendTaskABC`

Message send task with a defined duration and period.

**Parameters**

- **message** (`can.Message`) – The message to be sent periodically.



- **period** (*float*) – The rate in seconds at which to send the message.
- **duration** (*float*) – The duration to keep sending this message at given rate.

**class** `can.broadcastmanager.MultiRateCyclicSendTaskABC` (*channel*, *message*, *count*,  
*initial\_period*, *subsequent\_period*)

Bases: `can.broadcastmanager.CyclicSendTaskABC`

A Cyclic send task that supports switches send frequency after a set time.

Transmits a message *count* times at *initial\_period* then continues to transmit message at *subsequent\_period*.

#### Parameters

- **channel** – See interface specific documentation.
- **message** (`can.Message`) –
- **count** (*int*) –
- **initial\_period** (*float*) –
- **subsequent\_period** (*float*) –

**class** `can.ModifiableCyclicTaskABC` (*message*, *period*)

Bases: `can.broadcastmanager.CyclicSendTaskABC`

Adds support for modifying a periodic message

#### Parameters

- **message** (`can.Message`) – The message to be sent periodically.
- **period** (*float*) – The rate in seconds at which to send the message.

**modify\_data** (*message*)

Update the contents of this periodically sent message without altering the timing.

**Parameters** **message** (`can.Message`) – The message with the new `can.Message.data`.

Note: The arbitration ID cannot be changed.

**class** `can.RestartableCyclicTaskABC` (*message*, *period*)

Bases: `can.broadcastmanager.CyclicSendTaskABC`

Adds support for restarting a stopped cyclic task

#### Parameters

- **message** (`can.Message`) – The message to be sent periodically.
- **period** (*float*) – The rate in seconds at which to send the message.

**start** ()

Restart a stopped periodic task.

## Functional API

**Warning:** The functional API in `can.broadcastmanager.send_periodic()` is now deprecated and will be removed in version 4.0. Use the object oriented API via `can.BusABC.send_periodic()` instead.

`can.broadcastmanager.send_periodic` (*bus*, *message*, *period*, *\*args*, *\*\*kwargs*)

Send a *Message* every *period* seconds on the given bus.

**Parameters**

- **bus** (`can.BusABC`) – A CAN bus which supports sending.
- **message** (`can.Message`) – Message to send periodically.
- **period** (`float`) – The minimum time between sending messages.

**Returns** A started task instance

## 3.7 Internal API

Here we document the odds and ends that are more helpful for creating your own interfaces or listeners but generally shouldn't be required to interact with python-can.

### 3.7.1 Extending the `BusABC` class

Concrete implementations must implement the following:

- `send()` to send individual messages
- `_recv_internal()` to receive individual messages (see note below!)
- set the `channel_info` attribute to a string describing the underlying bus and/or channel

They might implement the following:

- `flush_tx_buffer()` to allow discarding any messages yet to be sent
- `shutdown()` to override how the bus should shut down
- `_send_periodic_internal()` to override the software based periodic sending and push it down to the kernel or hardware.
- `_apply_filters()` to apply efficient filters to lower level systems like the OS kernel or hardware.
- `_detect_available_configs()` to allow the interface to report which configurations are currently available for new connections.
- `state()` property to allow reading and/or changing the bus state.

---

**Note:** *TL;DR:* Only override `_recv_internal()`, never `recv()` directly.

Previously, concrete bus classes had to override `recv()` directly instead of `_recv_internal()`, but that has changed to allow the abstract base class to handle in-software message filtering as a fallback. All internal interfaces now implement that new behaviour. Older (custom) interfaces might still be implemented like that and thus might not provide message filtering:

---

Concrete instances are usually created by `can.Bus` which takes the users configuration into account.

### Bus Internals

Several methods are not documented in the main `can.BusABC` as they are primarily useful for library developers as opposed to library users. This is the entire ABC bus class with all internal methods:

**class** `can.BusABC` (*channel*, *can\_filters=None*, *\*\*config*)

Bases: `object`

The CAN Bus Abstract Base Class that serves as the basis for all concrete interfaces.

This class may be used as an iterator over the received messages.

Construct and open a CAN bus instance of the specified type.

Subclasses should call though this method with all given parameters as it handles generic tasks like applying filters.

#### Parameters

- **channel** – The can interface identifier. Expected type is backend dependent.
- **can\_filters** (*list*) – See `set_filters()` for details.
- **config** (*dict*) – Any backend dependent configurations are passed in this dictionary

**RECV\_LOGGING\_LEVEL = 9**

Log level for received messages

**\_\_init\_\_** (*channel*, *can\_filters=None*, *\*\*config*)

Construct and open a CAN bus instance of the specified type.

Subclasses should call though this method with all given parameters as it handles generic tasks like applying filters.

#### Parameters

- **channel** – The can interface identifier. Expected type is backend dependent.
- **can\_filters** (*list*) – See `set_filters()` for details.
- **config** (*dict*) – Any backend dependent configurations are passed in this dictionary

**\_\_iter\_\_** ()

Allow iteration on messages as they are received.

```
>>> for msg in bus:
...     print(msg)
```

**Yields** `can.Message` msg objects.

**\_\_metaclass\_\_**

alias of `abc.ABCMeta`

**\_\_str\_\_** ()

Return `str(self)`.

**\_\_weakref\_\_**

list of weak references to the object (if defined)

**\_\_apply\_filters** (*filters*)

Hook for applying the filters to the underlying kernel or hardware if supported/implemented by the interface.

**Parameters** **filters** (*Iterator[dict]*) – See `set_filters()` for details.

**static** **\_\_detect\_available\_configs** ()

Detect all configurations/channels that this interface could currently connect with.

This might be quite time consuming.

May not to be implemented by every interface on every platform.

**Return type** `Iterator[dict]`

**Returns** an iterable of dicts, each being a configuration suitable for usage in the interface's bus constructor.

**`_matches_filters`** (*msg*)

Checks whether the given message matches at least one of the current filters. See `set_filters()` for details on how the filters work.

This method should not be overridden.

**Parameters** `msg` (`can.Message`) – the message to check if matching

**Return type** `bool`

**Returns** whether the given message matches at least one filter

**`_recv_internal`** (*timeout*)

Read a message from the bus and tell whether it was filtered. This methods may be called by `recv()` to read a message multiple times if the filters set by `set_filters()` do not match and the call has not yet timed out.

New implementations should always override this method instead of `recv()`, to be able to take advantage of the software based filtering provided by `recv()` as a fallback. This method should never be called directly.

---

**Note:** This method is not an `@abstractmethod` (for now) to allow older external implementations to continue using their existing `recv()` implementation.

---

---

**Note:** The second return value (whether filtering was already done) may change over time for some interfaces, like for example in the Kvaser interface. Thus it cannot be simplified to a constant value.

---

**Parameters** `timeout` (*float*) – seconds to wait for a message, see `send()`

**Return type** `tuple[can.Message, bool]` or `tuple[None, bool]`

**Returns**

1. a message that was read or `None` on timeout
2. a bool that is `True` if message filtering has already been done and else `False`

**Raises**

- `can.CanError` – if an error occurred while reading
- `NotImplementedError` – if the bus provides it's own `recv()` implementation (legacy implementation)

**`_send_periodic_internal`** (*msg, period, duration=None*)

Default implementation of periodic message sending using threading.

Override this method to enable a more efficient backend specific approach.

**Parameters**

- `msg` (`can.Message`) – Message to transmit
- `period` (*float*) – Period in seconds between each message

- **duration** (*float*) – The duration to keep sending this message at given rate. If no duration is provided, the task will continue indefinitely.

**Returns** A started task instance. Note the task can be stopped (and depending on the backend modified) by calling the `stop()` method.

**Return type** *can.broadcastmanager.CyclicSendTaskABC*

**channel\_info** = 'unknown'

a string describing the underlying bus and/or channel

**filters**

Modify the filters of this bus. See *set\_filters()* for details.

**flush\_tx\_buffer()**

Discard every message that may be queued in the output buffer(s).

**recv** (*timeout=None*)

Block waiting for a message from the Bus.

**Parameters** **timeout** (*float or None*) – seconds to wait for a message or None to wait indefinitely

**Return type** *can.Message* or *None*

**Returns** None on timeout or a *can.Message* object.

**Raises** *can.CanError* – if an error occurred while reading

**send** (*msg, timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

**Parameters**

- **msg** (*can.Message*) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** *can.CanError* – if the message could not be sent

**send\_periodic** (*msg, period, duration=None, store\_task=True*)

Start sending a message at a given period on this bus.

The task will be active until one of the following conditions are met:

- the (optional) duration expires
- the Bus instance goes out of scope
- the Bus instance is shutdown
- *BusABC.stop\_all\_periodic\_tasks()* is called
- the task's *CyclicTask.stop()* method is called.

**Parameters**

- **msg** (*can.Message*) – Message to transmit
- **period** (*float*) – Period in seconds between each message

- **duration** (*float*) – The duration to keep sending this message at given rate. If no duration is provided, the task will continue indefinitely.
- **store\_task** (*bool*) – If True (the default) the task will be attached to this Bus instance. Disable to instead manage tasks manually.

**Returns** A started task instance. Note the task can be stopped (and depending on the backend modified) by calling the `stop()` method.

**Return type** *can.broadcastmanager.CyclicSendTaskABC*

---

**Note:** Note the duration before the message stops being sent may not be exactly the same as the duration specified by the user. In general the message will be sent at the given rate until at least **duration** seconds.

---

---

**Note:** For extremely long running Bus instances with many short lived tasks the default api with `store_task==True` may not be appropriate as the stopped tasks are still taking up memory as they are associated with the Bus instance.

---

**set\_filters** (*filters=None*)

Apply filtering to all messages received by this Bus.

All messages that match at least one filter are returned. If *filters* is *None* or a zero length sequence, all messages are matched.

Calling without passing any filters will reset the applied filters to *None*.

**Parameters filters** – A iterable of dictionaries each containing a “can\_id”, a “can\_mask”, and an optional “extended” key.

```
>>> [{"can_id": 0x11, "can_mask": 0x21, "extended": False}]
```

A filter matches, when `<received_can_id> & can_mask == can_id & can_mask`. If `extended` is set as well, it only matches messages where `<received_is_extended> == extended`. Else it matches every messages based only on the arbitration ID and mask.

**shutdown** ()

Called to carry out any interface specific cleanup required in shutting down a bus.

**state**

Return the current state of the hardware

**Returns** ACTIVE, PASSIVE or ERROR

**Return type** NamedTuple

**stop\_all\_periodic\_tasks** (*remove\_tasks=True*)

Stop sending any messages that were started using `bus.send_periodic`

**Parameters remove\_tasks** (*bool*) – Stop tracking the stopped tasks.

## 3.7.2 IO Utilities

Contains a generic class for file IO.

**class** `can.io.generic.BaseIOHandler` (*file*, *mode*='rt')

Bases: `object`

A generic file handler that can be used for reading and writing.

Can be used as a context manager.

**Attr file-like file** the file-like object that is kept internally, or *None* if none was opened

**Parameters**

- **file** – a path-like object to open a file, a file-like object to be used as a file or *None* to not use a file at all
- **mode** (*str*) – the mode that should be used to open the file, see `open()`, ignored if *file* is *None*

### 3.7.3 Other Util

Utilities and configuration file parsing.

`can.util.channel2int` (*channel*)

Try to convert the channel to an integer.

**Parameters** **channel** – Channel string (e.g. can0, CAN1) or integer

**Returns** Channel integer or *None* if unsuccessful

**Return type** `int`

`can.util.dlc2len` (*dlc*)

Calculate the data length from DLC.

**Parameters** **dlc** (*int*) – DLC (0-15)

**Returns** Data length in number of bytes (0-64)

**Return type** `int`

`can.util.len2dlc` (*length*)

Calculate the DLC from data length.

**Parameters** **length** (*int*) – Length in number of bytes (0-64)

**Returns** DLC (0-15)

**Return type** `int`

`can.util.load_config` (*path*=*None*, *config*=*None*, *context*=*None*)

Returns a dict with configuration details which is loaded from (in this order):

- config
- can.rc
- Environment variables CAN\_INTERFACE, CAN\_CHANNEL, CAN\_BITRATE
- Config files `/etc/can.conf` or `~/can` or `~/canrc` where the latter may add or replace values of the former.

Interface can be any of the strings from `can.VALID_INTERFACES` for example: kvaser, socketcan, pcan, usb2can, ixat, nican, virtual.

---

**Note:** The key `bustype` is copied to `interface` if that one is missing and does never appear in the result.

---

**Parameters**

- **path** – Optional path to config file.
- **config** – A dict which may set the ‘interface’, and/or the ‘channel’, or neither. It may set other values that are passed through.
- **context** – Extra ‘context’ pass to config sources. This can be use to section other than ‘default’ in the configuration file.

**Returns**

A config dictionary that should contain ‘interface’ & ‘channel’:

```
{
    'interface': 'python-can backend interface to use',
    'channel': 'default channel to use',
    # possibly more
}
```

Note None will be used if all the options are exhausted without finding a value.

All unused values are passed from config over to this.

**Raises** NotImplementedError if the interface isn’t recognized

`can.util.load_environment_config()`

Loads config dict from environmental variables (if set):

- CAN\_INTERFACE
- CAN\_CHANNEL
- CAN\_BITRATE

`can.util.load_file_config(path=None, section=None)`

Loads configuration from file with following content:

```
[default]
interface = socketcan
channel = can0
```

**Parameters**

- **path** – path to config file. If not specified, several sensible default locations are tried depending on platform.
- **section** – name of the section to read configuration from.

`can.util.set_logging_level(level_name=None)`

Set the logging level for the “can” logger. Expects one of: ‘critical’, ‘error’, ‘warning’, ‘info’, ‘debug’, ‘subdebug’

## 3.8 Utilities

## 3.9 Notifier

The Notifier object is used as a message distributor for a bus.



---

```
class can.Notifier (bus, listeners, timeout=1.0, loop=None)
```

```
Bases: object
```

```
Manages the distribution of can.Message instances to listeners.
```

```
Supports multiple busses and listeners.
```

---

**Note:** Remember to call `stop()` after all messages are received as many listeners carry out flush operations to persist data.

---

#### Parameters

- **bus** (`can.BusABC`) – A `Bus` or a list of buses to listen to.
- **listeners** (`list`) – An iterable of `Listener`
- **timeout** (`float`) – An optional maximum number of seconds to wait for any message.
- **loop** (`asyncio.AbstractEventLoop`) – An `asyncio` event loop to schedule listeners in.

```
add_bus (bus)
```

```
Add a bus for notification.
```

**Parameters** **bus** (`can.BusABC`) – CAN bus instance.

```
add_listener (listener)
```

```
Add new Listener to the notification list. If it is already present, it will be called two times each time a message arrives.
```

**Parameters** **listener** (`can.Listener`) – Listener to be added to the list to be notified

```
exception = None
```

```
Exception raised in thread
```

```
remove_listener (listener)
```

```
Remove a listener from the notification list. This method throws an exception if the given listener is not part of the stored listeners.
```

**Parameters** **listener** (`can.Listener`) – Listener to be removed from the list to be notified

**Raises** **ValueError** – if `listener` was never added to this notifier

```
stop (timeout=5)
```

```
Stop notifying Listeners when new Message objects arrive and call stop() on each Listener.
```

**Parameters** **timeout** (`float`) – Max time in seconds to wait for receive threads to finish.  
Should be longer than timeout given at instantiation.

## 3.10 Errors

```
class can.CanError
```

```
Bases: OSError
```

```
Indicates an error with the CAN network.
```



---

## CAN Interface Modules

---

**python-can** hides the low-level, device-specific interfaces to controller area network adapters in interface dependant modules. However as each hardware device is different, you should carefully go through your interface's documentation.

The available interfaces are:

### 4.1 SocketCAN

The full documentation for socketcan can be found in the kernel docs at [networking/can.txt](#).

---

**Note:** Versions before 2.2 had two different implementations named `socketcan_ctypes` and `socketcan_native`. These are now deprecated and the aliases to `socketcan` will be removed in version 4.0. 3.x releases raise a `DeprecationWarning`.

---

#### 4.1.1 Socketcan Quickstart

The CAN network driver provides a generic interface to setup, configure and monitor CAN devices. To configure bit-timing parameters use the program `ip`.

##### The virtual CAN driver (vcan)

The virtual CAN interfaces allow the transmission and reception of CAN frames without real CAN controller hardware. Virtual CAN network devices are usually named 'vcanX', like `vcan0` `vcan1` `vcan2`.

To create a virtual can interface using socketcan run the following:

```
sudo modprobe vcan
# Create a vcan network interface with a specific name
sudo ip link add dev vcan0 type vcan
sudo ip link set vcan0 up
```

## Real Device

`vcan` should be substituted for `can` and `vcan0` should be substituted for `can0` if you are using real hardware. Setting the bitrate can also be done at the same time, for example to enable an existing `can0` interface with a bitrate of 1MB:

```
sudo ip link set can0 up type can bitrate 1000000
```

## PCAN

Kernels  $\geq 3.4$  supports the PCAN adapters natively via *SocketCAN*, so there is no need to install any drivers. The CAN interface can be brought like so:

```
sudo modprobe peak_usb
sudo modprobe peak_pci
sudo ip link set can0 up type can bitrate 500000
```

## Send Test Message

The `can-utils` library for linux includes a script `cansend` which is useful to send known payloads. For example to send a message on `vcan0`:

```
cansend vcan0 123#DEADBEEF
```

## CAN Errors

A device may enter the “bus-off” state if too many errors occurred on the CAN bus. Then no more messages are received or sent. An automatic bus-off recovery can be enabled by setting the “restart-ms” to a non-zero value, e.g.:

```
sudo ip link set canX type can restart-ms 100
```

Alternatively, the application may realize the “bus-off” condition by monitoring CAN error frames and do a restart when appropriate with the command:

```
ip link set canX type can restart
```

Note that a restart will also create a CAN error frame.

## List network interfaces

To reveal the newly created `can0` or a `vcan0` interface:

```
ifconfig
```

## Display CAN statistics

```
ip -details -statistics link show vcan0
```

## Network Interface Removal

To remove the network interface:

```
sudo ip link del vcan0
```

### 4.1.2 Wireshark

Wireshark supports socketcan and can be used to debug *python-can* messages. Fire it up and watch your new interface.

To spam a bus:

```
import time
import can

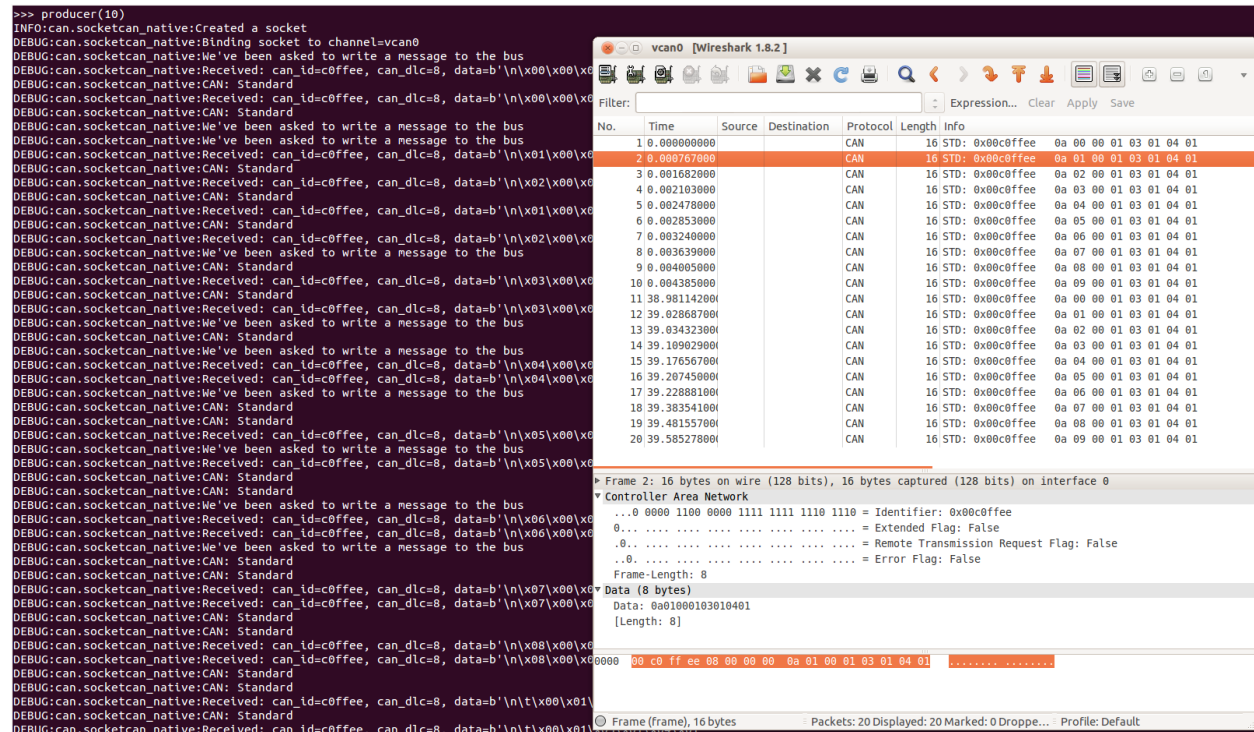
bustype = 'socketcan'
channel = 'vcan0'

def producer(id):
    """param id: Spam the bus with messages including the data id."""
    bus = can.interface.Bus(channel=channel, bustype=bustype)
    for i in range(10):
        msg = can.Message(arbitration_id=0xc0ffee, data=[id, i, 0, 1, 3, 1, 4, 1], is_
        ↪extended_id=False)
        bus.send(msg)

        time.sleep(1)

producer(10)
```

With debugging turned right up this looks something like this:



The process to follow bus traffic is even easier:

```
for message in Bus(can_interface):
    print(message)
```

### 4.1.3 Reading and Timeouts

Reading a single CAN message off of the bus is simple with the `bus.recv()` function:

```
import can

can_interface = 'vcan0'
bus = can.interface.Bus(can_interface, bustype='socketcan')
message = bus.recv()
```

By default, this performs a blocking read, which means `bus.recv()` won't return until a CAN message shows up on the socket. You can optionally perform a blocking read with a timeout like this:

```
message = bus.recv(1.0) # Timeout in seconds.

if message is None:
    print('Timeout occurred, no message.')
```

If you set the timeout to `0.0`, the read will be executed as non-blocking, which means `bus.recv(0.0)` will return immediately, either with a `Message` object or `None`, depending on whether data was available on the socket.

#### 4.1.4 Filtering

The implementation features efficient filtering of `can_id`'s. That filtering occurs in the kernel and is much much more efficient than filtering messages in Python.

### 4.1.5 Broadcast Manager

The `socketcan` interface implements thin wrappers to the linux *broadcast manager* socket api. This allows the cyclic transmission of CAN messages at given intervals. The overhead for periodic message sending is extremely low as all the heavy lifting occurs within the linux kernel.

#### `send_periodic()`

An example that uses the `send_periodic` is included in `python-can/examples/cyclic.py`

The object returned can be used to halt, alter or cancel the periodic message task.

```
class can.interfaces.socketcan.CyclicSendTask(bcm_socket, message, period, duration=None)
    Bases: can.broadcastmanager.LimitedDurationCyclicSendTaskABC, can.broadcastmanager.ModifiableCyclicTaskABC, can.broadcastmanager.RestartableCyclicTaskABC
```

A socketcan cyclic send task supports:

- setting of a task duration
- modifying the data
- stopping then subsequent restarting of the task

#### Parameters

- **bcm\_socket** – An open bcm socket on the desired CAN channel.
- **message** (`can.Message`) – The message to be sent periodically.
- **period** (`float`) – The rate in seconds at which to send the message.
- **duration** (`float`) – Approximate duration in seconds to send the message.

**modify\_data** (`message`)

Update the contents of this periodically sent message.

Note the Message must have the same `arbitration_id` like the first message.

**start** ()

Restart a stopped periodic task.

**stop** ()

Send a TX\_DELETE message to cancel this task.

This will delete the entry for the transmission of the CAN-message with the specified `can_id` CAN identifier. The message length for the command TX\_DELETE is `{bcm_msg_head}` (only the header).

### 4.1.6 Bus

```
class can.interfaces.socketcan.SocketcanBus(channel="", receive_own_messages=False, fd=False, **kwargs)
```

Bases: `can.bus.BusABC`

Implements `can.BusABC._detect_available_configs()`.

#### Parameters

- **channel** (*str*) – The can interface name with which to create this bus. An example channel would be ‘vcan0’ or ‘can0’. An empty string ‘’ will receive messages from all channels. In that case any sent messages must be explicitly addressed to a channel using `can.Message.channel`.
- **receive\_own\_messages** (*bool*) – If transmitted messages should also be received by this bus.
- **fd** (*bool*) – If CAN-FD frames should be supported.
- **can\_filters** (*list*) – See `can.BusABC.set_filters()`.

**recv** (*timeout=None*)

Block waiting for a message from the Bus.

**Parameters** **timeout** (*float*) – seconds to wait for a message or None to wait indefinitely

**Return type** `can.Message` or `None`

**Returns** None on timeout or a `can.Message` object.

**Raises** `can.CanError` – if an error occurred while reading

**send** (*msg, timeout=None*)

Transmit a message to the CAN bus.

**Parameters**

- **msg** (`can.Message`) – A message object.
- **timeout** (*float*) – Wait up to this many seconds for the transmit queue to be ready. If not given, the call may fail immediately.

**Raises** `can.CanError` – if the message could not be written.

**shutdown** ()

Stops all active periodic tasks and closes the socket.

## 4.2 Kvaser’s CANLIB

Kvaser’s CANLib SDK for Windows (also available on Linux).

### 4.2.1 Bus

**class** `can.interfaces.kvaser.canlib.KvaserBus` (*channel, can\_filters=None, \*\*config*)

Bases: `can.bus.BusABC`

The CAN Bus implemented for the Kvaser interface.

**Parameters**

- **channel** (*int*) – The Channel id to create this bus with.
- **can\_filters** (*list*) – See `can.BusABC.set_filters()`.

Backend Configuration

**Parameters**

- **bitrate** (*int*) – Bitrate of channel in bit/s
- **accept\_virtual** (*bool*) – If virtual channels should be accepted.



- **tseg1** (*int*) – Time segment 1, that is, the number of quanta from (but not including) the Sync Segment to the sampling point. If this parameter is not given, the Kvaser driver will try to choose all bit timing parameters from a set of defaults.
- **tseg2** (*int*) – Time segment 2, that is, the number of quanta from the sampling point to the end of the bit.
- **sjw** (*int*) – The Synchronization Jump Width. Decides the maximum number of time quanta that the controller can resynchronize every bit.
- **no\_samp** (*int*) – Either 1 or 3. Some CAN controllers can also sample each bit three times. In this case, the bit will be sampled three quanta in a row, with the last sample being taken in the edge between TSEG1 and TSEG2. Three samples should only be used for relatively slow baudrates.
- **driver\_mode** (*bool*) – Silent or normal.
- **single\_handle** (*bool*) – Use one Kvaser CANLIB bus handle for both reading and writing. This can be set if reading and/or writing is done from one thread.
- **receive\_own\_messages** (*bool*) – If messages transmitted should also be received back. Only works if single\_handle is also False. If you want to receive messages from other applications on the same computer, set this to True or set single\_handle to True.
- **fd** (*bool*) – If CAN-FD frames should be supported.
- **data\_bitrate** (*int*) – Which bitrate to use for data phase in CAN FD. Defaults to arbitration bitrate.

**flash** (*flash=True*)

Turn on or off flashing of the device's LED for physical identification purposes.

**flush\_tx\_buffer** ()

Wipeout the transmit buffer on the Kvaser.

**send** (*msg, timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (*can.Message*) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** *can.CanError* – if the message could not be sent

**shutdown** ()

Called to carry out any interface specific cleanup required in shutting down a bus.

## 4.2.2 Internals

The Kvaser *Bus* object with a physical CAN Bus can be operated in two modes; *single\_handle* mode with one shared bus handle used for both reading and writing to the CAN bus, or with two separate bus handles. Two separate handles are needed if receiving and sending messages are done in different threads (see [Kvaser documentation](#)).

**Warning:** Any objects inheriting from *Bus* should *not* directly use the interface `handle(s)`.

## Message filtering

The Kvaser driver and hardware only supports setting one filter per handle. If one filter is requested, this is will be handled by the Kvaser driver. If more than one filter is needed, these will be handled in Python code in the `recv` method. If a message does not match any of the filters, `recv()` will return `None`.

## Custom methods

This section contains Kvaser driver specific methods.

`KvaserBus.get_stats()`  
Retrieves the bus statistics.

Use like so:

```
>>> stats = bus.get_stats()
>>> print(stats)
std_data: 0, std_remote: 0, ext_data: 0, ext_remote: 0, err_frame: 0, bus_load: 0.
↳ 0%, overruns: 0
```

**Returns** bus statistics.

**Return type** `can.interfaces.kvaser.structures.BusStatistics`

## 4.3 CAN over Serial

A text based interface. For example use over serial ports like `/dev/ttyS1` or `/dev/ttyUSB0` on Linux machines or COM1 on Windows. Remote ports can be also used via a special URL. Both raw TCP sockets as also RFC2217 ports are supported: `socket://192.168.254.254:5000` or `rfc2217://192.168.254.254:5000`. In addition a virtual loopback can be used via `loop://` URL. The interface is a simple implementation that has been used for recording CAN traces.

---

**Note:** The properties **`extended_id`**, **`is_remote_frame`** and **`is_error_frame`** from the class:~`can.Message` are not in use. This interface will not send or receive flags for this properties.

---

### 4.3.1 Bus

**class** `can.interfaces.serial.serial_can.SerialBus(channel, baudrate=115200, time-out=0.1, rtscts=False, *args, **kwargs)`

Bases: `can.bus.BusABC`

Enable basic can communication over a serial device.

---

**Note:** See `can.interfaces.serial.SerialBus._recv_internal()` for some special semantics.

---

**Parameters**

- **channel** (*str*) – The serial device to open. For example “/dev/ttyS1” or “/dev/ttyUSB0” on Linux or “COM1” on Windows systems.
- **baudrate** (*int*) – Baud rate of the serial device in bit/s (default 115200).

**Warning:** Some serial port implementations don’t care about the baudrate.

- **timeout** (*float*) – Timeout for the serial device in seconds (default 0.1).
- **rtscts** (*bool*) – turn hardware handshake (RTS/CTS) on and off

**send** (*msg*, *timeout=None*)

Send a message over the serial device.

**Parameters**

- **msg** (*can.Message*) – Message to send.

**Note:** Flags like `extended_id`, `is_remote_frame` and `is_error_frame` will be ignored.

**Note:** If the timestamp is a float value it will be converted to an integer.

- **timeout** – This parameter will be ignored. The timeout value of the channel is used instead.

**shutdown** ()

Close the serial interface.

## 4.3.2 Internals

The frames that will be sent and received over the serial interface consist of six parts. The start and the stop byte for the frame, the timestamp, DLC, arbitration ID and the payload. The payload has a variable length of between 0 and 8 bytes, the other parts are fixed. Both, the timestamp and the arbitration ID will be interpreted as 4 byte unsigned integers. The DLC is also an unsigned integer with a length of 1 byte.

**Serial frame format**

	Start of frame	Timestamp	DLC	Arbitration ID	Pay-load	End of frame
<b>Length (Byte)</b>	1	4	1	4	0 - 8	1
<b>Data type</b>	Byte	Unsigned 4 byte integer	Unsigned 1 byte integer	Unsigned 4 byte integer	Byte	Byte
<b>Byte order</b>	-	Little-Endian	Little-Endian	Little-Endian	-	-
<b>Description</b>	Must be 0xAA	Usually s, ms or µs since start of the device	Length in byte of the payload	-	-	Must be 0xBB

## Examples of serial frames

### CAN message with 8 byte payload

CAN message	
Arbitration ID	Payload
1	0x11 0x22 0x33 0x44 0x55 0x66 0x77 0x88

Serial frame						
Start of frame	Timestamp	DLC	Arbitration ID	Payload	End of frame	
0xAA	0x66 0x73 0x00 0x00	0x08	0x01 0x00 0x00 0x00	0x11 0x22 0x33 0x44 0x55 0x66 0x77 0x88	0xBB	

### CAN message with 1 byte payload

CAN message	
Arbitration ID	Payload
1	0x11

Serial frame					
Start of frame	Timestamp	DLC	Arbitration ID	Payload	End of frame
0xAA	0x66 0x73 0x00 0x00	0x01	0x01 0x00 0x00 0x00	0x11	0xBB

### CAN message with 0 byte payload

CAN message	
Arbitration ID	Payload
1	None

Serial frame				
Start of frame	Timestamp	DLC	Arbitration ID	End of frame
0xAA	0x66 0x73 0x00 0x00	0x00	0x01 0x00 0x00 0x00	0xBBS

## 4.4 CAN over Serial / SLCAN

A text based interface: compatible to slcan-interfaces (slcan ASCII protocol) should also support LAWICEL direct. These interfaces can also be used with socketcan and slcand with Linux. This driver directly uses either the local or remote serial port, it makes slcan-compatible interfaces usable with Windows also. Remote serial ports will be specified via special URL. Both raw TCP sockets as also RFC2217 ports are supported.

Usage: use port or URL[@baurate] to open the device. For example use /dev/ttyUSB0@115200 or COM4@9600 for local serial ports and socket://192.168.254.254:5000 or rfc2217://192.168.254.254:5000 for remote ports.

### 4.4.1 Supported devices

---

**Todo:** Document this.

---

### 4.4.2 Bus

**class** `can.interfaces.slcan.slcanBus` (*channel*, *ttyBaudrate=115200*, *bitrate=None*,  
*sleep\_after\_open=2*, *rtscts=False*, *\*\*kwargs*)

Bases: `can.bus.BusABC`

slcan interface

#### Parameters

- **channel** (*str*) – port of underlying serial or usb device (e.g. `/dev/ttyUSB0`, `COM8`, ...)  
Must not be empty.
- **ttyBaudrate** (*int*) – baudrate of underlying serial or usb device
- **bitrate** (*int*) – Bitrate in bit/s
- **poll\_interval** (*float*) – Poll interval in seconds when reading messages
- **sleep\_after\_open** (*float*) – Time to wait in seconds after opening serial connection
- **rtscts** (*bool*) – turn hardware handshake (RTS/CTS) on and off

**send** (*msg*, *timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (`can.Message`) – A message object.
- **timeout** (*float or None*) – If  $> 0$ , wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. `None` blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown** ()

Called to carry out any interface specific cleanup required in shutting down a bus.

### 4.4.3 Internals

---

**Todo:** Document the internals of slcan interface.

---

## 4.5 IXXAT Virtual CAN Interface

Interface to [IXXAT](#) Virtual CAN Interface V3 SDK. Works on Windows.

The Linux ECI SDK is currently unsupported, however on Linux some devices are supported with [SocketCAN](#).

The `send_periodic()` method is supported natively through the on-board cyclic transmit list. Modifying cyclic messages is not possible. You will need to stop it, and then start a new periodic message.

## 4.5.1 Bus

### 4.5.2 Configuration file

The simplest configuration file would be:

```
[default]
interface = ixxat
channel = 0
```

Python-can will search for the first IXXAT device available and open the first channel. `interface` and `channel` parameters are interpreted by frontend `can.interfaces.interface` module, while the following parameters are optional and are interpreted by IXXAT implementation.

- `bitrate` (default 500000) Channel bitrate
- `UniqueHardwareId` (default first device) Unique hardware ID of the IXXAT device
- `rxFifoSize` (default 16) Number of RX mailboxes
- `txFifoSize` (default 16) Number of TX mailboxes
- `extended` (default False) Allow usage of extended IDs

### 4.5.3 Internals

The IXXAT *BusABC* object is a fairly straightforward interface to the IXXAT VCI library. It can open a specific device ID or use the first one found.

The frame exchange *do not involve threads* in the background but is explicitly instantiated by the caller.

- `recv()` is a blocking call with optional timeout.
- `send()` is not blocking but may raise a `VCLError` if the TX FIFO is full

RX and TX FIFO sizes are configurable with `rxFifoSize` and `txFifoSize` options, defaulting at 16 for both.

The CAN filters act as a “whitelist” in IXXAT implementation, that is if you supply a non-empty filter list you must explicitly state EVERY frame you want to receive (including RTR field). The `can_id/mask` must be specified according to IXXAT behaviour, that is bit 0 of `can_id/mask` parameters represents the RTR field in CAN frame. See IXXAT VCI documentation, section “Message filters” for more info.

## 4.6 PCAN Basic API

Interface to Peak-System’s PCAN-Basic API.

Windows driver: <https://www.peak-system.com/Downloads.76.0.html?&L=1>

Linux driver: <https://www.peak-system.com/fileadmin/media/linux/index.htm#download> and <https://www.peak-system.com/Downloads.76.0.html?&L=1> (PCAN-Basic API (Linux))

Mac driver: <http://www.mac-can.com>

### 4.6.1 Configuration

Here is an example configuration file for using [PCAN-USB](#):

```
[default]
interface = pcan
channel = PCAN_USBBUS1
state = can.bus.BusState.PASSIVE
bitrate = 500000
```

channel: (default PCAN\_USBBUS1) CAN interface name

state: (default can.bus.BusState.ACTIVE) BusState of the channel

bitrate: (default 500000) Channel bitrate

Valid channel values:

```
PCAN_ISABUSx
PCAN_DNGBUSx
PCAN_PCIBUSx
PCAN_USBBUSx
PCAN_PCCBUSx
PCAN_LANBUSx
```

Where x should be replaced with the desired channel number starting at 1.

### 4.6.2 Linux installation

Kernels >= 3.4 supports the PCAN adapters natively via [SocketCAN](#), refer to: [PCAN](#).

### 4.6.3 Bus

**class** can.interfaces.pcan.PcanBus (*channel='PCAN\_USBBUS1', state=<property object>, bitrate=500000, \*args, \*\*kwargs*)

Bases: can.bus.BusABC

A PCAN USB interface to CAN.

On top of the usual [Bus](#) methods provided, the PCAN interface includes the `flash()` and `status()` methods.

#### Parameters

- **channel** (*str*) – The can interface name. An example would be 'PCAN\_USBBUS1' Default is 'PCAN\_USBBUS1'
- **state** (*can.bus.BusState*) – BusState of the channel. Default is ACTIVE
- **bitrate** (*int*) – Bitrate of channel in bit/s. Default is 500 kbit/s.

#### flash (flash)

Turn on or off flashing of the device's LED for physical identification purposes.

#### reset ()

Command the PCAN driver to reset the bus after an error.

#### send (msg, timeout=None)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

**Parameters**

- **msg** (`can.Message`) – A message object.
- **timeout** (`float or None`) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown()**

Called to carry out any interface specific cleanup required in shutting down a bus.

**state**

Return the current state of the hardware

**Returns** ACTIVE, PASSIVE or ERROR

**Return type** NamedTuple

**status()**

Query the PCAN bus status.

**Return type** `int`

**Returns** The status code. See values in `basic.PCAN_ERROR_`

**status\_is\_ok()**

Convenience method to check that the bus status is OK

## 4.7 USB2CAN Interface

### 4.7.1 OVERVIEW

The `USB2CAN` is a cheap CAN interface based on an ARM7 chip (STR750FV2). There is support for this device on Linux through the `SocketCAN` interface and for Windows using this `usb2can` interface.

### 4.7.2 WINDOWS SUPPORT

Support though windows is achieved through a DLL very similar to the way the PCAN functions. The API is called CANAL (CAN Abstraction Layer) which is a separate project designed to be used with VSCP which is a socket like messaging system that is not only cross platform but also supports other types of devices. This device can be used through one of three ways 1)Through python-can 2)CANAL API either using the DLL and C/C++ or through the python wrapper that has been added to this project 3)VSCP Using python-can is strongly suggested as with little extra work the same interface can be used on both Windows and Linux.

### 4.7.3 WINDOWS INSTALL

1. To install on Windows download the USB2CAN Windows driver. It is compatible with XP, Vista, Win7, Win8/8.1. (Written against driver version v1.0.2.1)
2. Install the appropriate version of `pywin32` (win32com)



3. Download the USB2CAN CANAL DLL from the USB2CAN website. Place this in either the same directory you are running `usb2can.py` from or your DLL folder in your python install. Note that only a 32-bit version is currently available, so this only works in a 32-bit Python environment.

(Written against CANAL DLL version v1.0.6)

#### 4.7.4 Interface Layout

- **`usb2canabstractionlayer.py`** This file is only a wrapper for the CANAL API that the interface expects. There are also a couple of constants here to try and make dealing with the bitwise operations for flag setting a little easier. Other than that this is only the CANAL API. If a programmer wanted to work with the API directly this is the file that allows you to do this. The CANAL project does not provide this wrapper and normally must be accessed with C.
- **`usb2canInterface.py`** This file provides the translation to and from the python-can library to the CANAL API. This is where all the logic is and setup code is. Most issues if they are found will be either found here or within the DLL that is provided
- **`serial_selector.py`** See the section below for the reason for adding this as it is a little odd. What program does is if a serial number is not provided to the `usb2canInterface` file this program does WMI (Windows Management Instrumentation) calls to try and figure out what device to connect to. It then returns the serial number of the device. Currently it is not really smart enough to figure out what to do if there are multiple devices. This needs to be changed if people are using more than one interface.

#### 4.7.5 Interface Specific Items

There are a few things that are kinda strange about this device and are not overly obvious about the code or things that are not done being implemented in the DLL.

1. **You need the Serial Number to connect to the device under Windows. This is part of the “setup string” that configures the**
  1. Use `usb2canWin.py` to find the serial number
  2. Look on the device and enter it either through a prompt/barcode scanner/hardcode it.(Not recommended)
  3. Reprogram the device serial number to something and do that for all the devices you own. (Really Not Recommended, can no longer use multiple devices on one computer)
2. In `usb2canabstractionlayer.py` there is a structure called `CanalMsg` which has a unsigned byte array of size 8. In the `usb2canInterface` file it passes in an unsigned byte array of size 8 also which if you pass less than 8 bytes in it stuffs it with extra zeros. So if the data “01020304” is sent the message would look like “0102030400000000”. There is also a part of this structure called `sizeData` which is the actual length of the data that was sent not the stuffed message (in this case would be 4). What then happens is although a message of size 8 is sent to the device only the length of information so the first 4 bytes of information would be sent. This is done because the DLL expects a length of 8 and nothing else. So to make it compatible that has to be sent through the wrapper. If `usb2canInterface` sent an array of length 4 with `sizeData` of 4 as well the array would throw an incompatible data type error. There is a Wireshark file posted in Issue #36 that demonstrates that the bus is only sending the data and not the extra zeros.
3. The masking features have not been implemented currently in the CANAL interface in the version currently on the USB2CAN website.

**Warning:** Currently message filtering is not implemented. Contributions are most welcome!

### 4.7.6 Bus

**class** `can.interfaces.usb2can.Usb2canBus` (*channel*, \**args*, \*\**kwargs*)

Bases: `can.bus.BusABC`

Interface to a USB2CAN Bus.

#### Parameters

- **channel** (*str*) – The device’s serial number. If not provided, Windows Management Instrumentation will be used to identify the first such device. The *kwarg serial* may also be used.
- **bitrate** (*int*) – Bitrate of channel in bit/s. Values will be limited to a maximum of 1000 Kb/s. Default is 500 Kbs
- **flags** (*int*) – Flags to directly pass to open function of the usb2can abstraction layer.

**send** (*msg*, *timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (`can.Message`) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK’ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown** ()

Shut down the device safely

### 4.7.7 Internals

**class** `can.interfaces.usb2can.Usb2CanAbstractionLayer`

Bases: `object`

A low level wrapper around the usb2can library.

Documentation: [http://www.8devices.com/media/products/usb2can/downloads/CANAL\\_API.pdf](http://www.8devices.com/media/products/usb2can/downloads/CANAL_API.pdf)

**blocking\_receive** (*handle*, *msg*, *timeout*)

**blocking\_send** (*handle*, *msg*, *timeout*)

**close** (*handle*)

**get\_library\_version** ()

**get\_statistics** (*handle*, *CanalStatistics*)

**get\_status** (*handle*, *CanalStatus*)

**get\_vendor\_string** ()

**get\_version** ()

**open** (*pConfigureStr*, *flags*)

**receive** (*handle*, *msg*)

`send(handle, msg)`

## 4.8 NI-CAN

This interface adds support for CAN controllers by [National Instruments](#).

**Warning:** NI-CAN only seems to support 32-bit architectures so if the driver can't be loaded on a 64-bit Python, try using a 32-bit version instead.

**Warning:** CAN filtering has not been tested thoroughly and may not work as expected.

### 4.8.1 Bus

**class** `can.interfaces.nican.NicanBus` (*channel*, *can\_filters=None*, *bitrate=None*, *log\_errors=True*, *\*\*kwargs*)

Bases: `can.bus.BusABC`

The CAN Bus implemented for the NI-CAN interface.

**Warning:** This interface does implement efficient filtering of messages, but the filters have to be set in `__init__()` using the `can_filters` parameter. Using `set_filters()` does not work.

#### Parameters

- **channel** (*str*) – Name of the object to open (e.g. 'CAN0')
- **bitrate** (*int*) – Bitrate in bits/s
- **can\_filters** (*list*) – See `can.BusABC.set_filters()`.
- **log\_errors** (*bool*) – If True, communication errors will appear as CAN messages with `is_error_frame` set to True and `arbitration_id` will identify the error (default True)

**Raises** `can.interfaces.nican.NicanError` – If starting communication fails

#### **reset()**

Resets network interface. Stops network interface, then resets the CAN chip to clear the CAN error counters (clear error passive state). Resetting includes clearing all entries from read and write queues.

#### **send(msg, timeout=None)**

Send a message to NI-CAN.

**Parameters** `msg` (`can.Message`) – Message to send

**Raises** `can.interfaces.nican.NicanError` – If writing to transmit buffer fails. It does not wait for message to be ACKed currently.

#### **set\_filters(can\_filters=None)**

Unsupported. See note on `NicanBus`.

**shutdown()**

Close object.

**exception** `can.interfaces.nican.NicanError` (*function, error\_code, arguments*)

Bases: `can.CanError`

Error from NI-CAN driver.

**arguments = None**

Arguments passed to function

**error\_code = None**

Status code

**function = None**

Function that failed

## 4.9 isCAN

Interface for isCAN from [Thorsis Technologies GmbH](#), former ifak system GmbH.

### 4.9.1 Bus

**class** `can.interfaces.iscan.IscanBus` (*channel, bitrate=500000, poll\_interval=0.01, \*\*kwargs*)

Bases: `can.bus.BusABC`

isCAN interface

#### Parameters

- **channel** (*int*) – Device number
- **bitrate** (*int*) – Bitrate in bits/s
- **poll\_interval** (*float*) – Poll interval in seconds when reading messages

**send** (*msg, timeout=None*)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (`can.Message`) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown()**

Called to carry out any interface specific cleanup required in shutting down a bus.

**exception** `can.interfaces.iscan.IscanError` (*function, error\_code, arguments*)

Bases: `can.CanError`

## 4.10 NEOVI Interface

**Warning:** This ICS NeoVI documentation is a work in progress. Feedback and revisions are most welcome!

Interface to [Intrepid Control Systems](#) neoVI API range of devices via [python-ics](#) wrapper on Windows.

### 4.10.1 Installation

This neovi interface requires the installation of the ICS neoVI DLL and [python-ics](#) package.

- **Download and install the Intrepid Product Drivers** [Intrepid Product Drivers](#)
- **Install python-ics**

```
pip install python-ics
```

### 4.10.2 Configuration

An example *can.ini* file for windows 7:

```
[default]
interface = neovi
channel = 1
```

### 4.10.3 Bus

**class** `can.interfaces.ics_neovi.NeoViBus` (*channel*, *can\_filters=None*, *\*\*config*)

Bases: `can.bus.BusABC`

The CAN Bus implemented for the [python\\_ics](#) interface [https://github.com/intrepidcs/python\\_ics](https://github.com/intrepidcs/python_ics)

#### Parameters

- **channel** (*int* or *str* or *list(int)* or *list(str)*) – The channel ids to create this bus with. Can also be a single integer, netid name or a comma separated string.
- **can\_filters** (*list*) – See `can.BusABC.set_filters()` for details.
- **receive\_own\_messages** (*bool*) – If transmitted messages should also be received by this bus.
- **use\_system\_timestamp** (*bool*) – Use system timestamp for can messages instead of the hardware time stamp
- **serial** (*str*) – Serial to connect (optional, will use the first found if not supplied)
- **bitrate** (*int*) – Channel bitrate in bit/s. (optional, will enable the auto bitrate feature if not supplied)
- **fd** (*bool*) – If CAN-FD frames should be supported.
- **data\_bitrate** (*int*) – Which bitrate to use for data phase in CAN FD. Defaults to arbitration bitrate.

- **override\_library\_name** – Absolute path or relative path to the library including file-name.

**static** `get_serial_number(device)`

Decode (if needed) and return the ICS device serial string

**Parameters** `device` – ics device

**Returns** ics device serial string

**Return type** `str`

**send** (`msg`, `timeout=None`)

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

**Parameters**

- **msg** (`can.Message`) – A message object.
- **timeout** (`float` or `None`) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown** ()

Called to carry out any interface specific cleanup required in shutting down a bus.

## 4.11 Vector

This interface adds support for CAN controllers by [Vector](#).

By default this library uses the channel configuration for CANalyzer. To use a different application, open Vector Hardware Config program and create a new application and assign the channels you may want to use. Specify the application name as `app_name='Your app name'` when constructing the bus or in a config file.

Channel should be given as a list of channels starting at 0.

Here is an example configuration file connecting to CAN 1 and CAN 2 for an application named “python-can”:

```
[default]
interface = vector
channel = 0, 1
app_name = python-can
```

If you are using Python 2.7 it is recommended to install [pywin32](#), otherwise a slow and CPU intensive polling will be used when waiting for new messages.

### 4.11.1 Bus

```
class can.interfaces.vector.VectorBus(channel, can_filters=None, poll_interval=0.01,
                                       receive_own_messages=False, bitrate=None,
                                       rx_queue_size=16384, app_name='CANalyzer', se-
                                       rial=None, fd=False, data_bitrate=None, sjwAbr=2,
                                       tseg1Abr=6, tseg2Abr=3, sjwDbr=2, tseg1Dbr=6,
                                       tseg2Dbr=3, **config)
```

Bases: `can.bus.BusABC`

The CAN Bus implemented for the Vector interface.

#### Parameters

- **channel** (*list*) – The channel indexes to create this bus with. Can also be a single integer or a comma separated string.
- **poll\_interval** (*float*) – Poll interval in seconds.
- **bitrate** (*int*) – Bitrate in bits/s.
- **rx\_queue\_size** (*int*) – Number of messages in receive queue (power of 2). CAN: range 16...32768 CAN-FD: range 8192...524288
- **app\_name** (*str*) – Name of application in Hardware Config. If set to None, the channel should be a global channel index.
- **serial** (*int*) – Serial number of the hardware to be used. If set, the channel parameter refers to the channels ONLY on the specified hardware. If set, the app\_name is unused.
- **fd** (*bool*) – If CAN-FD frames should be supported.
- **data\_bitrate** (*int*) – Which bitrate to use for data phase in CAN FD. Defaults to arbitration bitrate.

**flush\_tx\_buffer()**

Discard every message that may be queued in the output buffer(s).

**send(msg, timeout=None)**

Transmit a message to the CAN bus.

Override this method to enable the transmit path.

#### Parameters

- **msg** (`can.Message`) – A message object.
- **timeout** (*float or None*) – If > 0, wait up to this many seconds for message to be ACK'ed or for transmit queue to be ready depending on driver implementation. If timeout is exceeded, an exception will be raised. Might not be supported by all interfaces. None blocks indefinitely.

**Raises** `can.CanError` – if the message could not be sent

**shutdown()**

Called to carry out any interface specific cleanup required in shutting down a bus.

**exception** `can.interfaces.vector.VectorError` (*error\_code, error\_string, function*)

Bases: `can.CanError`

## 4.12 Virtual

The virtual interface can be used as a way to write OS and driver independent tests.

A virtual CAN bus that can be used for automatic tests. Any Bus instances connecting to the same channel (in the same python program) will get each others messages.

```
import can

bus1 = can.interface.Bus('test', bustype='virtual')
bus2 = can.interface.Bus('test', bustype='virtual')

msg1 = can.Message(arbitration_id=0xabcde, data=[1,2,3])
bus1.send(msg1)
msg2 = bus2.recv()

assert msg1 == msg2
```

## 4.13 CANalyst-II

CANalyst-II(+) is a USB to CAN Analyzer. The controlcan library is originally developed by [ZLG ZHIYUAN Electronics](#).

### 4.13.1 Bus

```
class can.interfaces.canalystii.CANalystIIBus(channel, device=0, baud=None,
                                              Timing0=None, Timing1=None,
                                              can_filters=None)
```

Bases: `can.bus.BusABC`

#### Parameters

- **channel** – channel number
- **device** – device number
- **baud** – baud rate
- **Timing0** – customize the timing register if baudrate is not specified
- **Timing1** –
- **can\_filters** – filters for packet

**flush\_tx\_buffer()**

Discard every message that may be queued in the output buffer(s).

**send(msg, timeout=None)**

#### Parameters

- **msg** – message to send
- **timeout** – timeout is not used here

#### Returns

**shutdown()**

Called to carry out any interface specific cleanup required in shutting down a bus.



## 4.14 SYSTEC interface

Windows interface for the USBCAN devices supporting up to 2 channels based on the particular product. There is support for the devices also on Linux through the *SocketCAN* interface and for Windows using this *systec* interface.

### 4.14.1 Installation

The interface requires installation of the **USBCAN32.dll** library. Download and install the driver for specific **SYSTEC** device.

### 4.14.2 Supported devices

The interface supports following devices:

- GW-001 (obsolete),
- GW-002 (obsolete),
- Multiport CAN-to-USB G3,
- USB-CANmodul1 G3,
- USB-CANmodul2 G3,
- USB-CANmodul8 G3,
- USB-CANmodul16 G3,
- USB-CANmodul1 G4,
- USB-CANmodul2 G4.

### 4.14.3 Bus

**class** `can.interfaces.systec.ucanbus.UcanBus` (*channel*, *can\_filters=None*, *\*\*config*)  
 Bases: `can.bus.BusABC`

The CAN Bus implemented for the SYSTEC interface.

#### Parameters

- **channel** (*int*) – The Channel id to create this bus with.
- **can\_filters** (*list*) – See `can.BusABC.set_filters()`.

Backend Configuration

#### Parameters

- **bitrate** (*int*) – Channel bitrate in bit/s. Default is 500000.
- **device\_number** (*int*) – The device number of the USB-CAN. Valid values: 0 through 254. Special value 255 is reserved to detect the first connected device (should only be used, in case only one module is connected to the computer). Default is 255.
- **state** (`can.bus.BusState`) – BusState of the channel. Default is ACTIVE.
- **receive\_own\_messages** (*bool*) – If messages transmitted should also be received back. Default is False.

- **rx\_buffer\_entries** (*int*) – The maximum number of entries in the receive buffer. Default is 4096.
- **tx\_buffer\_entries** (*int*) – The maximum number of entries in the transmit buffer. Default is 4096.

**Raises**

- **ValueError** – If invalid input parameter were passed.
- **can.CanError** – If hardware or CAN interface initialization failed.

**static create\_filter** (*extended, from\_id, to\_id, rtr\_only, rtr\_too*)

Calculates AMR and ACR using CAN-ID as parameter.

**Parameters**

- **extended** (*bool*) – if True parameters from\_id and to\_id contains 29-bit CAN-ID
- **from\_id** (*int*) – first CAN-ID which should be received
- **to\_id** (*int*) – last CAN-ID which should be received
- **rtr\_only** (*bool*) – if True only RTR-Messages should be received, and rtr\_too will be ignored
- **rtr\_too** (*bool*) – if True CAN data frames and RTR-Messages should be received

**Returns** Returns list with one filter containing a “can\_id”, a “can\_mask” and “extended” key.

**flush\_tx\_buffer** ()

Flushes the transmit buffer.

**Raises** **can.CanError** – If flushing of the transmit buffer failed.

**send** (*msg, timeout=None*)

Sends one CAN message.

When a transmission timeout is set the firmware tries to send a message within this timeout. If it could not be sent the firmware sets the “auto delete” state. Within this state all transmit CAN messages for this channel will be deleted automatically for not blocking the other channel.

**Parameters**

- **msg** (*can.Message*) – The CAN message.
- **timeout** (*float*) – Transmit timeout in seconds (value 0 switches off the “auto delete”)

**Raises** **can.CanError** – If the message could not be sent.

**shutdown** ()

Shuts down all CAN interfaces and hardware interface.

**state**

Return the current state of the hardware

**Returns** ACTIVE, PASSIVE or ERROR

**Return type** NamedTuple

## 4.14.4 Configuration

The simplest configuration would be:

```
interface = sysrec
channel = 0
```

Python-can will search for the first device found if not specified explicitly by the `device_number` parameter. The `interface` and `channel` are the only mandatory parameters. The interface supports two channels 0 and 1. The maximum number of entries in the receive and transmit buffer can be set by the parameters `rx_buffer_entries` and `tx_buffer_entries`, with default value 4096 set for both.

Optional parameters:

- `bitrate` (default 500000) Channel bitrate in bit/s
- `device_number` (default first device) The device number of the USB-CAN
- `rx_buffer_entries` (default 4096) The maximum number of entries in the receive buffer
- `tx_buffer_entries` (default 4096) The maximum number of entries in the transmit buffer
- `state` (default `BusState.ACTIVE`) `BusState` of the channel
- `receive_own_messages` (default `False`) If messages transmitted should also be received back

## 4.14.5 Internals

### Message filtering

The interface and driver supports only setting of one filter per channel. If one filter is requested, this is will be handled by the driver itself. If more than one filter is needed, these will be handled in Python code in the `recv` method. If a message does not match any of the filters, `recv()` will return `None`.

### Periodic tasks

The driver supports periodic message sending but without the possibility to set the interval between messages. Therefore the handling of the periodic messages is done by the interface using the `ThreadBasedCyclicSendTask`.

Additional interfaces can be added via a plugin interface. An external package can register a new interface by using the `can.interface` entry point in its `setup.py`.

The format of the entry point is `interface_name=module:classname` where `classname` is a concrete `can.BusABC` implementation.

```
entry_points={
    'can.interface': [
        "interface_name=module:classname",
    ]
},
```

The *Interface Names* are listed in [Configuration](#).



The following modules are callable from python-can.

They can be called for example by `python -m can.logger` or `can_logger.py` (if installed using pip).

## 5.1 can.logger

Command line help, called with `--help`:

```
$ python -m can.logger -h
usage: python -m can.logger [-h] [-f LOG_FILE] [-v] [-c CHANNEL]
                             [-i {serial,neovi,socketcan_native,kvaser,pcan,nican,
↳ iscan,usb2can,ixxat,systec,socketcan,socketcan_ctypes,slcan,vector,canalystii,
↳ virtual}]
                             [--filter ...] [-b BITRATE] [--active | --passive]

Log CAN traffic, printing messages to stdout or to a given file.

optional arguments:
  -h, --help                show this help message and exit
  -f LOG_FILE, --file_name LOG_FILE
                             Path and base log filename, for supported types see
                             can.Logger.
  -v                        How much information do you want to see at the command
                             line? You can add several of these e.g., -vv is DEBUG
  -c CHANNEL, --channel CHANNEL
                             Most backend interfaces require some sort of channel.
                             For example with the serial interface the channel
                             might be a rfcomm device: "/dev/rfcomm0" With the
                             socketcan interfaces valid channel examples include:
                             "can0", "vcan0"
  -i {serial,neovi,socketcan_native,kvaser,pcan,nican,iscan,usb2can,ixxat,systec,
↳ socketcan,socketcan_ctypes,slcan,vector,canalystii,virtual}, --interface {serial,
↳ neovi,socketcan_native,kvaser,pcan,nican,iscan,usb2can,ixxat,systec,socketcan,
↳ socketcan_ctypes,slcan,vector,canalystii,virtual}
```

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```

--filter ...          Specify the backend CAN interface to use. If left
                      blank, fall back to reading from configuration files.
                      Comma separated filters can be specified for the given
                      CAN interface: <can_id>:<can_mask> (matches when
                      <received_can_id> & mask == can_id & mask)
                      <can_id>~<can_mask> (matches when <received_can_id> &
                      mask != can_id & mask)
-b BITRATE, --bitrate BITRATE
                      Bitrate to use for the CAN bus.
--active              Start the bus as active, this is applied the default.
--passive             Start the bus as passive.

```

## 5.2 can.player

```

$ python -m can.player -h
usage: python -m can.player [-h] [-f LOG_FILE] [-v] [-c CHANNEL]
                           [-i {socketcan_native,ixxat,socketcan,nican,iscan,
socketcan_ctypes,serial,neovi,sysrec,kvaser,vector,canalystii,virtual,usb2can,pcan,
slcan}]
                           [-b BITRATE] [--ignore-timestamps] [-g GAP]
                           [-s SKIP]
                           input-file

Replay CAN traffic.

positional arguments:
  input-file            The file to replay. For supported types see
                        can.LogReader.

optional arguments:
  -h, --help            show this help message and exit
  -f LOG_FILE, --file_name LOG_FILE
                        Path and base log filename, for supported types see
                        can.LogReader.
  -v                    Also print can frames to stdout. You can add several
                        of these to enable debugging
  -c CHANNEL, --channel CHANNEL
                        Most backend interfaces require some sort of channel.
                        For example with the serial interface the channel
                        might be a rfcomm device: "/dev/rfcomm0" With the
                        socketcan interfaces valid channel examples include:
                        "can0", "vcan0"
  -i {socketcan_native,ixxat,socketcan,nican,iscan,socketcan_ctypes,serial,neovi,
sysrec,kvaser,vector,canalystii,virtual,usb2can,pcan,slcan}, --interface {socketcan_
native,ixxat,socketcan,nican,iscan,socketcan_ctypes,serial,neovi,sysrec,kvaser,
vector,canalystii,virtual,usb2can,pcan,slcan}
                        Specify the backend CAN interface to use. If left
                        blank, fall back to reading from configuration files.
  -b BITRATE, --bitrate BITRATE
                        Bitrate to use for the CAN bus.
  --ignore-timestamps   Ignore timestamps (send all frames immediately with
                        minimum gap between frames)
  -g GAP, --gap GAP     <s> minimum time between replayed frames
  -s SKIP, --skip SKIP  <s> skip gaps greater than 's' seconds

```

## 5.3 can.viewer

A screenshot of the application can be seen below:

Count	Time	dt	ID	DLC	Data	Parsed values
14	118.884757	39.110070	0x004	8	00 01 00 00 00 00 00 00	
510	123.283816	0.249922	0x080	0		
1177	123.354005	0.117875	0x104	8	02 00 00 00 11 00 70 00	2 0.170000 64.171273
1177	123.352952	0.117906	0x105	8	A4 72 6D 42 11 D3 91 41	59.361954 18.228060
133	123.345939	1.062629	0x106	8	0E BF 57 BC FB 63 2A 3F	-0.013168 0.665588
133	123.346099	1.062508	0x107	8	B7 84 22 C1 1C 75 44 BC	-10.157401 -0.687023
133	123.346326	1.062497	0x108	8	35 E7 31 BD FB 7A F4 3A	-2.488550 0.106870
133	123.346985	1.062441	0x109	8	EC DF B7 BD F2 84 1D 3F	-0.089783 0.615310
133	123.347096	1.062339	0x10A	8	2D 44 1E C1 3D 6F 14 3C	-9.891644 0.5190840
133	123.347336	1.062343	0x10B	8	7C 04 E3 3B BB BF EB BB	0.396947 -0.4122148
133	123.347931	1.062645	0x10C	8	EF D5 62 3B 92 5F 16 BB	0.198314 -0.1314669
133	123.348112	1.062670	0x10D	8	60 B2 F8 BB 82 46 4E 3A	-0.434853 0.0450850
133	123.348338	1.062648	0x10E	8	B4 01 71 BB C0 5F 51 BA	-0.210703 -0.045762
133	123.352078	1.062858	0x10F	8	27 16 09 42 49 09 03 42	34.271633 32.759068
1177	123.354920	0.117775	0x110	8	1D DD 96 BB DA CC 1C BB	-0.263790 -0.137085
1177	123.358016	0.117962	0x119	8	00 00 00 00 D8 58 A8 41	0.000000 21.043381
1177	123.355925	0.117854	0x11F	8	B8 13 02 BC 91 B4 BF BB	-0.454887 -0.335202
133	123.349015	1.062675	0x121	8	6F 7E E1 3B 38 51 28 BD	0.394282 -2.3544608
133	123.349107	1.062563	0x122	8	1B E6 A0 BB 83 B9 43 BC	
133	123.349331	1.062556	0x123	8	7C 51 B3 3B 11 7F 55 3B	
133	123.349958	1.062847	0x124	8	E0 1B 47 BE 5E 14 47 3E	
133	123.350154	1.062819	0x125	8	E1 A3 1C C1 AB 75 8A BE	
133	123.350350	1.062782	0x126	8	F7 43 15 3E 8D 68 18 C1	
133	123.340031	1.062874	0x140	8	5E 95 1E 96 EF 95 60 00	3.823800 3.843000 3.838300 96
133	123.340937	1.062782	0x141	6	01 01 08 05 65 0E	1 1 8 5 368.500000
133	123.341941	1.062762	0x142	8	12 04 01 1A 01 07 60 00	18 4 1 26 1 7 96
133	123.342946	1.062771	0x143	8	00 00 00 00 8A 22 25 04	0.000000 88.420000 106.100000
133	123.343936	1.062737	0x144	8	01 C0 0F 46 00 00 00 0F	1 403.200000 7.000000 0 0 15
133	123.344893	1.062669	0x145	5	00 00 00 00 00	0.000000 0.000000 0
510	123.294528	0.259875	0x181	8	00 00 00 00 00 00 00 00	0 0.000000 0
510	123.284057	0.249957	0x201	8	00 00 00 00 00 00 00 00	
65	122.035098	2.499398	0x281	7	0B 00 0F 00 1E 00 01	11 15 30 100.000000
510	123.284230	0.249805	0x301	6	00 00 00 00 00 00	
65	122.035354	2.499410	0x381	8	50 04 00 00 CD 16 00 00	
1252	123.434077	0.100077	0x701	1	05	
1251	123.410814	0.099982	0x702	1	05	
1241	123.388151	0.100562	0x715	1	05	
2486	123.433095	0.049963	0x77E	1	05	
2486	123.432953	0.049914	0x77F	1	05	
1251	123.392075	0.099990	0x0000007B	4	00 00 00 00	
1251	123.391466	0.099862	0x00000097B	8	00 00 00 00 00 00 00 00	0.000000 0.000000 0.000000
1251	123.391718	0.099909	0x000000E7B	8	0D FD 00 00 0A B8 DA E5	35.810000 0.000000 27.440000 -94.9900000

The first column is the number of times a frame with the particular ID that has been received, next is the timestamp of the frame relative to the first received message. The third column is the time between the current frame relative to the previous one. Next is the length of the frame, the data and then the decoded data converted according to the `-d` argument. The top red row indicates an error frame.

### 5.3.1 Command line arguments

By default the `can.viewer` uses the *SocketCAN* interface. All interfaces are supported and can be specified using the `-i` argument or configured following *Configuration*.

The full usage page can be seen below:

```
$ python -m can.viewer -h
Usage: python -m can.viewer [-h] [--version] [-b BITRATE] [-c CHANNEL]
                        [-d {<id>:<format>,<id>:<format>:<scaling1>:...:<scalingN>
↳ ,file.txt}]
                        [-f {<can_id>:<can_mask>,<can_id>~<can_mask>}]
                        [-i {canalystii,iscan,ixxat,kvaser,neovi,nican,pcan,
↳ serial,slcan,socketcan,socketcan_ctypes,socketcan_native,systec,usb2can,vector,
↳ virtual}]
```

A simple CAN viewer terminal application written in Python

Optional arguments:

```
-h, --help                Show this help message and exit
--version                Show program's version number and exit
-b, --bitrate BITRATE    Bitrate to use for the given CAN interface
-c, --channel CHANNEL    Most backend interfaces require some sort of channel.
                        For example with the serial interface the channel
                        might be a rfcomm device: "/dev/rfcomm0" with the
                        socketcan interfaces valid channel examples include:
                        "can0", "vcan0". (default: use default for the
                        specified interface)
-d, --decode {<id>:<format>,<id>:<format>:<scaling1>:...:<scalingN>,file.txt}
                        Specify how to convert the raw bytes into real values.
                        The ID of the frame is given as the first argument and the
↳ format as the second.
                        The Python struct package is used to unpack the received data
                        where the format characters have the following meaning:
                        < = little-endian, > = big-endian
                        x = pad byte
                        c = char
                        ? = bool
                        b = int8_t, B = uint8_t
                        h = int16, H = uint16
                        l = int32_t, L = uint32_t
                        q = int64_t, Q = uint64_t
                        f = float (32-bits), d = double (64-bits)
                        Fx to convert six bytes with ID 0x100 into uint8_t, uint16_
↳ and uint32_t:
                        $ python -m can.viewer -d "100:<BHL"
                        Note that the IDs are always interpreted as hex values.
                        An optional conversion from integers to real units can be
↳ given
                        as additional arguments. In order to convert from raw integer
                        values the values are divided with the corresponding scaling_
↳ value,
                        similarly the values are multiplied by the scaling value in_
↳ order
                        to convert from real units to raw integer values.
                        Fx lets say the uint8_t needs no conversion, but the uint16_
↳ and the uint32_t
```

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```

needs to be divided by 10 and 100 respectively:
$ python -m can.viewer -d "101:<BHL:1:10.0:100.0"
Be aware that integer division is performed if the scaling_
↪value is an integer.

Multiple arguments are separated by spaces:
$ python -m can.viewer -d "100:<BHL" "101:<BHL:1:10.0:100.0"
Alternatively a file containing the conversion strings_
↪separated by new lines
can be given as input:
$ cat file.txt
100:<BHL
101:<BHL:1:10.0:100.0
$ python -m can.viewer -d file.txt
-f, --filter {<can_id>:<can_mask>,<can_id>~<can_mask>}
Space separated CAN filters for the given CAN interface:
<can_id>:<can_mask> (matches when <received_can_id> &_
↪mask == can_id & mask)
<can_id>~<can_mask> (matches when <received_can_id> &_
↪mask != can_id & mask)
Fx to show only frames with ID 0x100 to 0x103 and 0x200 to_
↪0x20F:
python -m can.viewer -f 100:7FC 200:7F0
Note that the ID and mask are always interpreted as hex values
-i, --interface {canalystii,iscan,ixxat,kvaser,neovi,nican,pcan,serial,slcan,
↪socketcan,socketcan_ctypes,socketcan_native,sysrec,usb2can,vector,virtual}
Specify the backend CAN interface to use.

```

## Shortcuts:

Key	Description
ESQ/q	Exit the viewer
c	Clear the stored frames
s	Sort the stored frames
SPACE	Pause the viewer
UP/DOWN	Scroll the viewer



### 6.1 Contributing

Contribute to source code, documentation, examples and report issues: <https://github.com/hardbyte/python-can>

There is also a [python-can](#) mailing list for development discussion.

### 6.2 Building & Installing

The following assumes that the commands are executed from the root of the repository:

- The project can be built and installed with `python setup.py build` and `python setup.py install`.
- The unit tests can be run with `python setup.py test`. The tests can be run with `python2`, `python3`, `pypy` or `pypy3` to test with other python versions, if they are installed. Maybe, you need to execute `pip3 install python-can[test]` (or only `pip` for Python 2), if some dependencies are missing.
- The docs can be built with `sphinx-build doc/ doc/_build`. Appending `-n` to the command makes Sphinx complain about more subtle problems.

### 6.3 Creating a new interface/backend

These steps are a guideline on how to add a new backend to python-can.

- Create a module (either a `*.py` or an entire subdirectory depending on the complexity) inside `can.interfaces`
- Implement the central part of the backend: the bus class that extends `can.BusABC`. See [Extending the BusABC class](#) for more info on this one!

- Register your backend bus class in `can.interface.BACKENDS` and `can.interfaces.VALID_INTERFACES` in `can.interfaces.__init__.py`.
- Add docs where appropriate. At a minimum add to `doc/interfaces.rst` and add a new interface specific document in `doc/interface/*`.
- Update `doc/scripts.rst` accordingly.
- Add tests in `test/*` where appropriate.

## 6.4 Code Structure

The modules in `python-can` are:

Module	Description
<i>interfaces</i>	Contains interface dependent code.
<i>bus</i>	Contains the interface independent Bus object.
<i>message</i>	Contains the interface independent Message object.
<i>io</i>	Contains a range of file readers and writers.
<i>broadcastmanager</i>	Contains interface independent broadcast manager code.
<i>CAN</i>	Legacy API. Deprecated.

## 6.5 Creating a new Release

- Release from the `master` branch.
- Update the library version in `__init__.py` using [semantic versioning](#).
- Check if any deprecations are pending.
- Run all tests and examples against available hardware.
- Update *CONTRIBUTORS.txt* with any new contributors.
- For larger changes update `doc/history.rst`.
- Sanity check that documentation has stayed inline with code.
- Create a temporary virtual environment. Run `python setup.py install` and `python setup.py test`.
- Create and upload the distribution: `python setup.py sdist bdist_wheel`.
- Sign the packages with `gpg` `gpg --detach-sign -a dist/python-can-X.Y.Z-py3-none-any.whl`.
- Upload with `twine` `twine upload dist/python-can-X.Y.Z*`.
- In a new virtual env check that the package can be installed with `pip`: `pip install python-can==X.Y.Z`.
- Create a new tag in the repository.
- Check the release on PyPi, Read the Docs and GitHub.

---

## History and Roadmap

---

### 7.1 Background

Originally written at [Dynamic Controls](#) for internal use testing and prototyping wheelchair components.

Maintenance was taken over and the project was open sourced by Brian Thorne in 2010.

### 7.2 Acknowledgements

Originally written by Ben Powell as a thin wrapper around the Kvaser SDK to support the leaf device.

Support for linux socketcan was added by Rose Lu as a summer coding project in 2011. The socketcan interface was helped immensely by Phil Dixon who wrote a leaf-socketcan driver for Linux.

The pcan interface was contributed by Albert Bloomfield in 2013. Support for pcan on Mac was added by Kristian Sloth Lauszus in 2018.

The usb2can interface was contributed by Joshua Villyard in 2015.

The IXXAT VCI interface was contributed by Giuseppe Corbelli and funded by [Weightpack](#) in 2016.

The NI-CAN and virtual interfaces plus the ASCII and BLF loggers were contributed by Christian Sandberg in 2016 and 2017. The BLF format is based on a C++ library by Toby Lorenz.

The slcan interface, ASCII listener and log logger and listener were contributed by Eduard Bröcker in 2017.

The NeoVi interface for ICS (Intrepid Control Systems) devices was contributed by Pierre-Luc Tessier Gagné in 2017.

Many improvements all over the library, cleanups, unifications as well as more comprehensive documentation and CI testing was contributed by Felix Divo in 2017 and 2018.

The CAN viewer terminal script was contributed by Kristian Sloth Lauszus in 2018.

The CANalyst-II interface was contributed by Shaoyu Meng in 2018.

## 7.3 Support for CAN within Python

Python natively supports the CAN protocol from version 3.3 on, if running on Linux:

Python version	Feature	Link
3.3	Initial SocketCAN support	<a href="#">Docs</a>
3.4	Broadcast Management (BCM) commands are natively supported	<a href="#">Docs</a>
3.5	CAN FD support	<a href="#">Docs</a>
3.7	Support for CAN ISO-TP	<a href="#">Docs</a>

## CHAPTER 8

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### Known Bugs

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See the project [bug tracker](#) on github. Patches and pull requests very welcome!

---

**Documentation generated**

Feb 25, 2019

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### C

- `can`, [13](#)
- `can.broadcastmanager`, [25](#)
- `can.io.generic`, [34](#)
- `can.util`, [35](#)



## Symbols

`__iter__()` (*can.BusABC* method), 10  
`__str__()` (*can.Message* method), 15

## A

`add_bus()` (*can.Notifier* method), 37  
`add_listener()` (*can.Notifier* method), 37  
`arbitration_id` (*can.Message* attribute), 14  
`arguments` (*can.interfaces.nican.NicanError* attribute), 56  
`ASCReader` (class in *can*), 22  
`ASCWriter` (class in *can*), 22  
`AsyncBufferedReader` (class in *can*), 18

## B

`BaseIOHandler` (class in *can.io.generic*), 34  
`bitrate_switch` (*can.Message* attribute), 15  
`BLFReader` (class in *can*), 24  
`BLFWriter` (class in *can*), 23  
`blocking_receive()`  
     (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
     method), 54  
`blocking_send()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
     method), 54  
`BufferedReader` (class in *can*), 17  
`Bus` (class in *can*), 9  
`BusABC` (class in *can*), 10

## C

`can` (module), 13  
`can.broadcastmanager` (module), 25  
`can.io.generic` (module), 34  
`can.util` (module), 35  
`CANalystIIBus` (class in *can.interfaces.canalystii*),  
     60  
`CanError` (class in *can*), 37  
`CanutilsLogReader` (class in *can*), 23  
`CanutilsLogWriter` (class in *can*), 23  
`channel` (*can.Message* attribute), 15

`channel2int()` (in module *can.util*), 35  
`channel_info` (*can.BusABC* attribute), 10  
`close()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
     method), 54  
`COMPRESSION_LEVEL` (*can.BLFWriter* attribute), 24  
`create_filter()` (*can.interfaces.sysrec.ucanbus.UcanBus*  
     static method), 62  
`CSVReader` (class in *can*), 20  
`CSVWriter` (class in *can*), 19  
`CyclicSendTask` (class in *can.interfaces.socketcan*),  
     43  
`CyclicSendTaskABC` (class in  
     *can.broadcastmanager*), 28  
`CyclicTask` (class in *can.broadcastmanager*), 28

## D

`data` (*can.Message* attribute), 14  
`dlc` (*can.Message* attribute), 14  
`dlc2len()` (in module *can.util*), 35

## E

`equals()` (*can.Message* method), 16  
`error_code` (*can.interfaces.nican.NicanError* attribute), 56  
`error_state_indicator` (*can.Message* attribute),  
     15  
`exception` (*can.Notifier* attribute), 37

## F

`filters` (*can.BusABC* attribute), 10  
`flash()` (*can.interfaces.kvaser.canlib.KvaserBus*  
     method), 45  
`flash()` (*can.interfaces.pcan.PcanBus* method), 51  
`flush_tx_buffer()` (*can.BusABC* method), 10  
`flush_tx_buffer()`  
     (*can.interfaces.canalystii.CANalystIIBus*  
     method), 60  
`flush_tx_buffer()`  
     (*can.interfaces.kvaser.canlib.KvaserBus*  
     method), 45

`flush_tx_buffer()`  
(*can.interfaces.sysrec.ucanbus.UcanBus*  
method), 62

`flush_tx_buffer()`  
(*can.interfaces.vector.VectorBus* method),  
59

`function` (*can.interfaces.nican.NicanError* attribute),  
56

## G

`get_library_version()`  
(*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

`get_message()` (*can.AsyncBufferedReader* method),  
18

`get_message()` (*can.BufferedReader* method), 17

`GET_MESSAGE_TIMEOUT` (*can.SqliteWriter* attribute),  
21

`get_serial_number()`  
(*can.interfaces.ics\_neovi.NeoViBus* static  
method), 58

`get_statistics()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

`get_stats()` (*can.interfaces.kvaser.canlib.KvaserBus*  
method), 46

`get_status()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

`get_vendor_string()`  
(*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

`get_version()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

## I

`is_error_frame` (*can.Message* attribute), 15

`is_extended_id` (*can.Message* attribute), 15

`is_fd` (*can.Message* attribute), 15

`is_remote_frame` (*can.Message* attribute), 15

`IscanBus` (class in *can.interfaces.iscan*), 56

`IscanError`, 56

## K

`KvaserBus` (class in *can.interfaces.kvaser.canlib*), 44

## L

`len2dlc()` (in module *can.util*), 35

`LimitedDurationCyclicSendTaskABC` (class in  
*can.broadcastmanager*), 28

`Listener` (class in *can*), 16

`load_config()` (in module *can.util*), 35

`load_environment_config()` (in module  
*can.util*), 36

`load_file_config()` (in module *can.util*), 36

`log_event()` (*can.ASCWriter* method), 22

`log_event()` (*can.BLFWriter* method), 24

`Logger` (class in *can*), 18

## M

`MAX_BUFFER_SIZE_BEFORE_WRITES`  
(*can.SqliteWriter* attribute), 21

`MAX_CACHE_SIZE` (*can.BLFWriter* attribute), 24

`MAX_TIME_BETWEEN_WRITES` (*can.SqliteWriter* at-  
tribute), 21

`Message` (class in *can*), 13

`ModifiableCyclicTaskABC` (class in *can*), 29

`modify_data()` (*can.interfaces.socketcan.CyclicSendTask*  
method), 43

`modify_data()` (*can.ModifiableCyclicTaskABC*  
method), 29

`MultiRateCyclicSendTaskABC` (class in  
*can.broadcastmanager*), 29

## N

`NeoViBus` (class in *can.interfaces.ics\_neovi*), 57

`NicanBus` (class in *can.interfaces.nican*), 55

`NicanError`, 56

`Notifier` (class in *can*), 36

## O

`on_error()` (*can.Listener* method), 17

`on_message_received()` (*can.ASCWriter* method),  
22

`on_message_received()`  
(*can.AsyncBufferedReader* method), 18

`on_message_received()` (*can.BLFWriter* method),  
24

`on_message_received()` (*can.BufferedReader*  
method), 18

`on_message_received()` (*can.CanutilsLogWriter*  
method), 23

`on_message_received()` (*can.CSVWriter* method),  
20

`on_message_received()` (*can.Listener* method),  
17

`on_message_received()` (*can.Printer* method), 19

`open()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

## P

`PcanBus` (class in *can.interfaces.pcan*), 51

`Printer` (class in *can*), 19

## R

`read_all()` (*can.SqliteReader* method), 21

`receive()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer*  
method), 54

`recv()` (*can.BusABC* method), 10

`recv()` (*can.interfaces.socketcan.SocketcanBus* method), 44  
`RECV_LOGGING_LEVEL` (*can.BusABC* attribute), 10  
`remove_listener()` (*can.Notifier* method), 37  
`reset()` (*can.interfaces.nican.NicanBus* method), 55  
`reset()` (*can.interfaces.pcan.PcanBus* method), 51  
`RestartableCyclicTaskABC` (class in *can*), 29

## S

`send()` (*can.BusABC* method), 10  
`send()` (*can.interfaces.canalystii.CANalystIIBus* method), 60  
`send()` (*can.interfaces.ics\_neovi.NeoViBus* method), 58  
`send()` (*can.interfaces.iscan.IscanBus* method), 56  
`send()` (*can.interfaces.kvaser.canlib.KvaserBus* method), 45  
`send()` (*can.interfaces.nican.NicanBus* method), 55  
`send()` (*can.interfaces.pcan.PcanBus* method), 51  
`send()` (*can.interfaces.serial.serial\_can.SerialBus* method), 47  
`send()` (*can.interfaces.slcan.slcanBus* method), 49  
`send()` (*can.interfaces.socketcan.SocketcanBus* method), 44  
`send()` (*can.interfaces.systec.ucanbus.UcanBus* method), 62  
`send()` (*can.interfaces.usb2can.Usb2CanAbstractionLayer* method), 54  
`send()` (*can.interfaces.usb2can.Usb2canBus* method), 54  
`send()` (*can.interfaces.vector.VectorBus* method), 59  
`send_periodic()` (*can.BusABC* method), 11  
`send_periodic()` (in module *can.broadcastmanager*), 29  
`SerialBus` (class in *can.interfaces.serial.serial\_can*), 46  
`set_filters()` (*can.BusABC* method), 11  
`set_filters()` (*can.interfaces.nican.NicanBus* method), 55  
`set_logging_level()` (in module *can.util*), 36  
`shutdown()` (*can.BusABC* method), 12  
`shutdown()` (*can.interfaces.canalystii.CANalystIIBus* method), 60  
`shutdown()` (*can.interfaces.ics\_neovi.NeoViBus* method), 58  
`shutdown()` (*can.interfaces.iscan.IscanBus* method), 56  
`shutdown()` (*can.interfaces.kvaser.canlib.KvaserBus* method), 45  
`shutdown()` (*can.interfaces.nican.NicanBus* method), 55  
`shutdown()` (*can.interfaces.pcan.PcanBus* method), 52  
`shutdown()` (*can.interfaces.serial.serial\_can.SerialBus* method), 47  
`shutdown()` (*can.interfaces.slcan.slcanBus* method), 49  
`shutdown()` (*can.interfaces.socketcan.SocketcanBus* method), 44  
`shutdown()` (*can.interfaces.systec.ucanbus.UcanBus* method), 62  
`shutdown()` (*can.interfaces.usb2can.Usb2canBus* method), 54  
`shutdown()` (*can.interfaces.vector.VectorBus* method), 59  
`slcanBus` (class in *can.interfaces.slcan*), 49  
`SocketcanBus` (class in *can.interfaces.socketcan*), 43  
`SqliteReader` (class in *can*), 21  
`SqliteWriter` (class in *can*), 20  
`start()` (*can.interfaces.socketcan.CyclicSendTask* method), 43  
`start()` (*can.RestartableCyclicTaskABC* method), 29  
`state` (*can.BusABC* attribute), 12  
`state` (*can.interfaces.pcan.PcanBus* attribute), 52  
`state` (*can.interfaces.systec.ucanbus.UcanBus* attribute), 62  
`status()` (*can.interfaces.pcan.PcanBus* method), 52  
`status_is_ok()` (*can.interfaces.pcan.PcanBus* method), 52  
`stop()` (*can.ASCWriter* method), 22  
`stop()` (*can.BLFWriter* method), 24  
`stop()` (*can.broadcastmanager.CyclicTask* method), 28  
`stop()` (*can.BufferedReader* method), 18  
`stop()` (*can.interfaces.socketcan.CyclicSendTask* method), 43  
`stop()` (*can.Listener* method), 17  
`stop()` (*can.Notifier* method), 37  
`stop()` (*can.SqliteReader* method), 21  
`stop()` (*can.SqliteWriter* method), 21  
`stop_all_periodic_tasks()` (*can.BusABC* method), 12

## T

`ThreadSafeBus` (class in *can*), 13  
`timestamp` (*can.Message* attribute), 14

## U

`UcanBus` (class in *can.interfaces.systec.ucanbus*), 61  
`Usb2CanAbstractionLayer` (class in *can.interfaces.usb2can*), 54  
`Usb2canBus` (class in *can.interfaces.usb2can*), 54

## V

`VectorBus` (class in *can.interfaces.vector*), 59  
`VectorError`, 59