
AdafruitDRV2605 Library Documentation

Release 1.0

Tony DiCola

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CircuitPython module for the DRV2605 haptic feedback motor driver.

CHAPTER 1

Dependencies

This driver depends on:

- [Adafruit CircuitPython](#)
- [Bus Device](#)

Please ensure all dependencies are available on the CircuitPython filesystem. This is easily achieved by downloading the [Adafruit library and driver bundle](#).

CHAPTER 2

Usage Example

See `examples/simpletest.py` for a demo of the usage.

3.1 Adafruit_DRV2605

CircuitPython module for the DRV2605 haptic feedback motor driver. See examples/simpletest.py for a demo of the usage.

- Author(s): Tony DiCola

class `adafruit_drv2605.DRV2605` (*i2c*, *address*=<*sphinx.ext.autodoc._MockObject object*>)
TI DRV2605 haptic feedback motor driver module.

library

Get and set the library selected for waveform playback. Should be a value of: - `LIBRARY_EMPTY`: Empty - `LIBRARY_TS2200A`: TS2200 library A (the default) - `LIBRARY_TS2200B`: TS2200 library B - `LIBRARY_TS2200C`: TS2200 library C - `LIBRARY_TS2200D`: TS2200 library D - `LIBRARY_TS2200E`: TS2200 library E - `LIBRARY_LRA`: LRA library See the datasheet for the meaning and description of effects in each library.

mode

Get and set the mode of the chip. Should be a value of:

- `MODE_INTTRIG`: Internal triggering, vibrates as soon as you call `play()`. Default mode.
- `MODE_EXTRIGEDGE`: External triggering, edge mode.
- `MODE_EXTRIGLVL`: External triggering, level mode.
- `MODE_PWMANALOG`: PWM/analog input mode.
- `MODE_AUDIOVIBE`: Audio-to-vibration mode.
- `MODE_REALTIME`: Real-time playback mode.
- `MODE_DIAGNOS`: Diagnostics mode.
- `MODE_AUTOCAL`: Auto-calibration mode.

See the datasheet for the meaning of modes beyond `MODE_INTTRIG`.

play()

Play back the select effect(s) on the motor.

set_waveform (*effect_id*, *slot=0*)

Select an effect waveform for the specified slot (default is slot 0, but up to 7 effects can be combined with slot values 0 to 6). See the datasheet for a complete table of effect ID values and the associated waveform / effect.

stop()

Stop vibrating the motor.

use_ERM()

Use an eccentric rotating mass motor (the default).

use_LRM()

Use a linear resonance actuator motor.

CHAPTER 4

Contributing

Contributions are welcome! Please read our [Code of Conduct](#) before contributing to help this project stay welcoming.

CHAPTER 5

Building locally

To build this library locally you'll need to install the `circuitpython-build-tools` package.

```
python3 -m venv .env
source .env/bin/activate
pip install circuitpython-build-tools
```

Once installed, make sure you are in the virtual environment:

```
source .env/bin/activate
```

Then run the build:

```
circuitpython-build-bundles --filename_prefix adafruit-circuitpython-drv2605 --
↳library_location .
```


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