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# **automate Documentation**

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## Introduction

### What is Automate?

Automate is a general purpose automatization library for Python. Its objective is to offer convenient and robust object-oriented programming framework for complex state machine systems. Automate can be used to design complex automation systems, yet it is easy to learn and fun to use. It was originally developed with home robotics/automatization projects in mind, but is quite general in nature and one could find applications from various fields that could take advantage of Automate. Automate can be embedded in other Python software as a component, which runs its operations in its own threads.

### Highlights

- Supported hardware:
  - Raspberry Pi GPIO input/output ports (*Raspberry Pi GPIO Support for Automate* via RPIO library)
  - Arduino analog and digital input/output ports (*Arduino Support for Automate* via pyFirmata library)
  - Easy to write extensions to support other hardware, see *Making your own Automate Extensions*
- *System State Saving and Restoring via Serialization*
- Intelligent design:
  - Comprehensively tested via `py.test` unit/integration tests
  - Takes advantage of `Traits` library, especially its notification system.
  - `IPython` console to monitor, modify and control system on-the-fly
  - Versatile function/callable library to write state program logic
- RPC and Websocket interfaces (provided by *Remote Procedure Call Support for Automate* and *Web User Interface for Automate*) to connect between other applications or other Automate systems.

- Comprehensive and customizable Web User Interface via *Web User Interface for Automate*
- UML graphs can be drawn automatically of the system (as can be seen in the examples of this documentation)

## “Hello World” in Automate

Let us consider following short Automate program as a first example:

```
from automate import *

class MySystem(System):
    # HW switch connected Raspberry Pi GPIO port 1
    hardware_switch = RpioSensor(port=1)
    # Switch that is controllable, for example, from WEB interface
    web_switch = UserBoolSensor()
    # Lamp relay that switches lamp on/off, connected to GPIO port 2
    lamp = RpioActuator(port=2)
    # Program that controls the system behaviour
    program = Program(
        active_condition=Or('web_switch', 'hardware_switch'),
        on_activate=SetStatus('lamp', True)
    )

my_system = MySystem(
    services=[WebService()]
)
```

This simple example has two sensors `hardware_switch`, `web_switch`, actuator (lamp) and a program that contains logic what to do and when. Here, lamp is switched on if either `web_switch` or `hardware_switch` has status `True`. `WebService` with default settings is enabled so that user can monitor system and set status of `web_switch`. The following figure (generated via `WebService` interface) illustrates the system in UML graph:

## Original application

Automate was originally developed in order to enable simple and robust way of programming home automatization with [Raspberry Pi](#) minicomputer, to obtain automatization and automatic monitoring of rather complex planted aquarium safety/controlling system.

## How to Install Automate?

Automate can be installed like ordinary python package. I recommend installation in within virtual environment (see [virtualenv](#)).

1. (optional): Create and start using `virtualenv`:

```
mkvirtualenv automate
workon automate
```

2. Install from pypi:

```
pip install automate
```

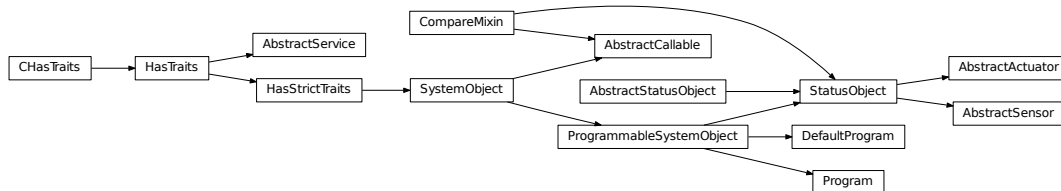
Optionally, you can specify some of the extras, i.e. web, rpc, raspberrypi, arduino:

```
pip install automate[web,rpc,raspberrypi,arduino]
```

or if you want them all:

```
pip install automate[all]
```

## Automate Components



Automate system is built of the following components:

- **System** (derived by user from *System*) binds all parts together into a single state machine
- **Services** (subclassed of *AbstractService*) provide programming interfaces with user and devices that can be used by **SystemObjects**.
- **SystemObjects** (subclassed of *SystemObject* or *ProgrammableSystemObject*):
  - **Sensors** (subclassed on *AbstractSensor*) are used as an interface to the (usually read-only) state of device or software.
  - **Actuators** (subclassed on *AbstractActuator*) are used as an interface to set/write the state of device or software.
  - **Programs** (subclassed on *ProgrammableSystemObject*) define the logic between Sensors and Actuators. They are used to control statuses of Actuators, by rules that are programmed by using special **Callables** (subclasses of *AbstractCallable*) objects that depend on statuses of Sensors and other components. Also Sensors and Actuators are often subclassed from *ProgrammableSystemObject* so they also have similar features by themselves. Depending on the application, however, it might (or might not) improve readability if plain *Program* component is used.

All Automate components are derived from *HasTraits*, provided by Traits library, which provides automatic notification of attribute changes, which is used extensively in Automate. Due to traits, all Automate components are configured by passing attribute names as keyword arguments in object initialization (see for example attributes `pin` and `dev` traits of `ArduinoDigitalActuator` in the example below).

Automate system is written by subclassing *System* and adding there desired *SystemObject* as its attributes, such as in the following example:

```

from automate import *
class MySystem(System):
    mysensor = FloatSensor()
    myactuator = ArduinoDigitalActuator(pin=13, service=0)
    myprogram = Program()
    ...

```

After defining the system, it can be instantiated. There, services with their necessary arguments can be explicitly defined as follows:

```

mysys = MySystem(services=[WebService(http_port=8080), ArduinoService(device='/dev/
↳ttyS0')])

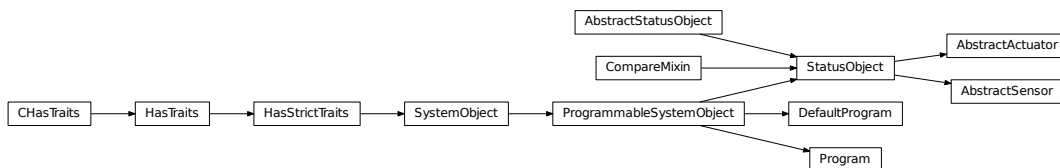
```

Some services (those that have *autoload* attribute set to True) do not need to be explicitly defined. For example, *ArduinoService* would be used automatically loaded because of the usage of *ArduinoDigitalActuator*, with default settings (*device='/dev/ttyUSB0'*). Instantiating *System* will launch IPython shell to access the system internals from the command line. This can be prevented, if necessary, by defining keyword argument *exclude\_services* as ['*TextUIService*'], which disables autoloading of *TextUIService*. For further information about services, see *Services*.

## Programming Automate Objects

### Programs

Program features are defined in *ProgrammableSystemObject* class. *Program*, *DefaultProgram* and *StatusObject* classes are subclassed from *ProgrammableSystemObject*, as can be seen in the following inheritance diagram.



Programs are used to define the logic on which system operates. Program behavior is determined by the conditions (*active\_condition*, *update\_condition*) and actions (*on\_activate*, *on\_update*, *on\_deactivate*), that are of *AbstractCallable* type. Callables are special objects that are used to implement the actual programming of Automate program objects (see *Callables*). There are many special Callable classes to perform different operations (see *Builtin Callables*) and it is also easy to develop your own Callables (see *Deriving Custom Callables*).

All Sensors and Actuators that affect the return value of a condition callable, are *triggers* of a Callable. All actuators (and writeable sensors) that a callable may change, are *targets*. Whenever any of the triggers status change, programs conditions are automatically updated and actions are taken if appropriate condition evaluates as True.

Actions and conditions are used as follows. Programs can be either active or inactive depending on *active\_condition*. When program activates (i.e. *active\_condition* changes to True), *on\_activate* action



is called. When program deactivates, `on_deactivate`, action is called, correspondingly. When program is active, its targets can be continuously manipulated by `on_update` callable, which is called whenever `update_condition` evaluates as `True`.

## Actuator Status Manipulation

Program can control status of one or more actuators. Programs manipulate Actuator statuses the following way:

- One or more programs can control state of the same Actuator. Each program has `priority` (floating point number), so that the actual status of Actuator is determined by program with highest priority
- If highest priority program deactivates, the control of Actuator status is moved to the the second-highest priority active program.
- If there are no other Program, each Actuator has also one `DefaultProgram`, which then takes over Actuator control.

The following example application illustrates the priorities:

```

from automate import *
class MySystem(System):
    low_prio_prg = UserBoolSensor(priority=-5,
                                  active_condition=Value('low_prio_prg'),
                                  on_activate=SetStatus('actuator', 1.0),
                                  default=True,
                                  )
    med_prio_prg = UserBoolSensor(priority=1,
                                   active_condition=Value('med_prio_prg'),
                                   on_activate=SetStatus('actuator', 2.0),
                                   default=True,
                                   )
    high_prio_prg = UserBoolSensor(priority=5,
                                    active_condition=Value('high_prio_prg'),
                                    on_activate=SetStatus('actuator', 3.0),
                                    default=True,
                                    )
    inactive_high_prio_prg = UserBoolSensor(priority=6,
                                             active_condition=Value('inactive_high_prio_prg'),
                                             on_activate=SetStatus('actuator', 4.0),
                                             default=False,
                                             )

    actuator = FloatActuator()

ms = MySystem(services=[WebService()])

```

In this application, four programs (three manually defined programs and `DefaultProgram dp_actuator`) are active for actuator. The actual status of actuator (now: 3.0) is determined by highest priority program. If `high_prio_prg` goes inactive (i.e. if its status is changed to `False`):

```
high_prio_prg.status = False
```

the status is then determined by `med_prio_prg` ( $\Rightarrow$  2.0). And so on. All the active programs for actuator are visible in UML diagram. Red arrow shows the dominating program, blue arrows show the other non-dominating active programs and gray arrows show the inactive programs that have the actuator as a target (i.e. if they are activated,

they will manipulate the status of the actuator). `low_prio_prg` can never manipulate actuator status as its priority is lower than default program `dp_actuator` priority.

## Program Features

Program features are defined in `ProgrammableSystemObject` class. Its definition is as follows:

---

**Note:** Unfortunately, due to current Sphinx autodoc limitation, all trait types are displayed in this documentation as `None`. For the real trait types, please see the source code.

---

**class** `automate.program.ProgrammableSystemObject` (*\*args, \*\*kwargs*)

System object with standard program features (i.e. conditions & actions).

**active\_condition = None**

A condition Callable which determines the condition, when the program is activated. Program deactivates, when condition turns to False. When program is activated, `on_activate` action is executed. When program deactivates, `on_deactivate` is executed.

**on\_activate = None**

An action Callable to be executed when Program activates.

**on\_deactivate = None**

An action Callable to be executed when Program deactivates.

**update\_condition = None**

When program is active, this is the condition Callable that must equal to `True` in order to `on_update` action to be executed. Whenever a trigger is changed, this condition is checked and if `True`, `on_update` is executed.

**on\_update = None**

Action Callable to be executed if Program is active and `update_condition` is `True`.

**priority = None**

When programs sets Actuator status, the actual status of Actuator is determined by a program that has highest priority. Lower priority programs are stacked and used only if higher priority programs are deactivated.

**active = None**

Is program active? Automatically changed. In UIs you can fake the program active status by changing this. Normally do not change manually.

**status = None**

Status property is introduced to have interface compability with Status objects. For plain Programs, status equals to the result of its active condition Callable.

**actual\_triggers = None**

(read-only property) Set of triggers, that cause this Program conditions to be checked (and actions to be executed). This data is updated from custom triggers list, conditions and actions.

**actual\_targets = None**

(read-only property) Set of targets that this Program might touch. This data is updated from custom targets list and actions.

**triggers = None**

Custom set of additional triggers, whose status change will trigger this Program conditions/actions

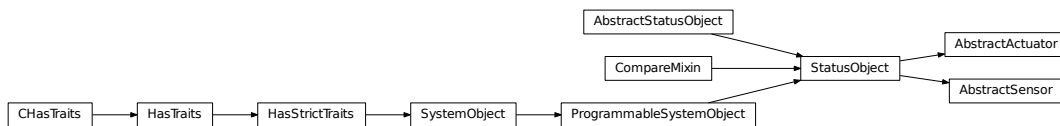
**exclude\_triggers = None**

Triggers in this set do not trigger the program actions/conditions even if they are introduced by Callables etc.

**targets = None**

Additional targets. Not usually needed, but if you want to set status for some reason by some custom function, for example, then you need to use this.

## StatusObjects



Actuators (*AbstractActuator*) and sensors (*AbstractSensor*) are subclassed of *StatusObject*. The most important property is *status*, which may be of various data types, depending of the implementation defined in subclasses. Type of status is determined by *\_status* trait.

There are couple of useful features in StatusObjects that may be used to affect when status is really changed. These are accessible via the following attributes:

- *safety\_delay* and *safety\_mode* can be used to define a minimum delay between status changes (“safety” ~ some devices might break if changed with big frequency)
- *change\_delay* and *change\_mode* can be used to define a delay which (always) takes place before status is changed.

Here, modes are one of 'rising', 'falling', 'both', default being 'rising'. To disable functionality completely, set corresponding delay parameter to zero. Functions are described below.

## Creating Custom Sensors and Actuators

Custom actuators and sensors can be easiliy written based on *AbstractActuator* and *AbstractSensor* classes, respectively.

As an example, we will define one of each:

```

# imports from your own library that you are using to define your sensor & actuator
from mylibrary import (setup_data_changed_callback,
                       fetch_data_from_my_datasource,
                       initialize_my_actuator_device,
                       change_status_in_my_actuator_device)

class MySensor(AbstractSensor):
    """
    Let us assume that you have your own library which has a status that you
    want to track in your Automate program.
    """
    # define your status data type
  
```

```

_status = CBool
def setup(self):
    setup_my_datasource()
    # we tell our library that update_status need to be called when status is
    # changed. We could use self.set_status directly, if library can pass
    # new status as an argument.
    setup_data_changed_callback(self.update_status)
def update_status(self):
    # fetch new status from your datasource (this function is called by
    # your library)
    self.status = fetch_data_from_your_datasource()
def cleanup(self):
    # define this if you need to clean things up when program is stopped
    pass

class MyActuator(AbstractActuator):
    # define your status data type. Transient=True is a good idea because
    # actuator status is normally determined by other values (sensors & programs etc)
    _status = CFloat(transient=True)
def setup(self):
    initialize_my_actuator_device()
def _status_changed(self):
    chagngge_status_in_my_actuator_device(self.status)

```

For more examples, look *builtin\_sensors* and *builtin\_actuators*. For more examples, see also *Extensions*, especially support modules for Arduino and Raspberry Pi IO devices)

## StatusObject Definition

**class** automate.statusobject.**StatusObject** (\*args, \*\*kwargs)

Baseclass for Sensors and Actuators

**safety\_delay = None**

Determines minimum time required for switching. State change is then delayed if necessary.

**safety\_mode = None**

Determines when *safety\_delay* needs to be taken into account: when status is rising, falling or both.

**change\_delay = None**

Similar to *safety\_delay*, but just delays change to make sure that events shorter than *change\_delay* are not taken into account

**change\_mode = None**

As *safety\_mode*, but for *change\_delay*

**silent = None**

Do not emit actuator status changes into logs

**debug = None**

Print more debugging information into logs

**changing = None**

(property) Is delayed change taking place at the moment?

**history\_transpose = None**

Transpose of history (timestamps, statuses)

**history\_length = None**

Amount of status change events to be stored in history

**history\_frequency = None**

How often new values are saved to history, in seconds

**is\_program**

A property which can be used to check if StatusObject uses program features or not.

**status = None**

Status of the object.

**get\_status\_display (\*\*kwargs)**

Define how status is displayed in UIs (add units etc.).

**get\_as\_datadict ()**

Get data of this object as a data dictionary. Used by websocket service.

**set\_status (new\_status, origin=None, force=False)**

For sensors, this is synonymous to:

```
sensor.status = new_status
```

For (non-slave) actuators, origin argument (i.e. is the program that is changing the status) need to be given,

**update\_status ()**

In sensors: implement particular value reading from device etc. here (this calls set\_status(value)). In actuators: set value in particular device. Implement in subclasses.

**activate\_program (program)**

When program controlling this object activates, it calls this function.

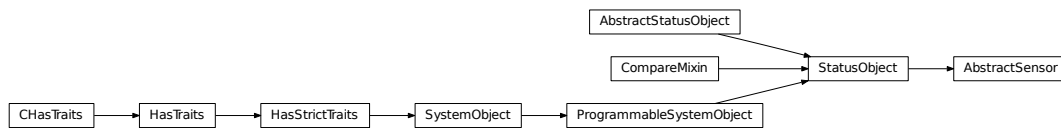
**deactivate\_program (program)**

When program controlling this object deactivates, it calls this function.

**get\_program\_status (program)**

Determine status of this object set by a particular program. Useful only for Actuators but defined here for interface compatibility.

## Sensor Baseclass Definition



**class** automate.statusobject.**AbstractSensor** (\*args, \*\*kwargs)

Base class for all sensors

**user\_editable = None**

Is sensor user-editable in UIs. This variable is meant for per-instance tuning for Sensors, whereas *editable* is for per-class adjustment.

**default = None**

Default value for status

**reset\_delay = None**

If non-zero, Sensor status will be reset to default after defined time (in seconds).

**silent = None**

Do not log status changes

**status\_filter = None**

Filter status with a function (lambdas are not serializable, don't use them if you are using system state saving)

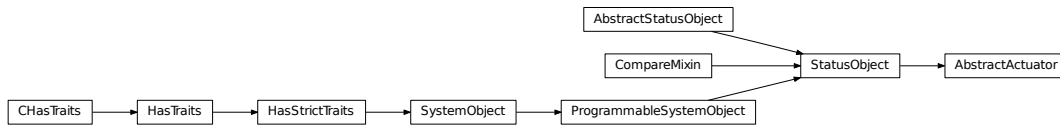
**set\_status (status, origin=None, force=False)**

Compatibility to actuator class. Also `setStatus` callable can be used for sensors too, if so desired.

**update\_status ()**

A method to read and update actual status. Implement it in subclasses, if necessary

## Actuator Baseclass Definition



**class** `automate.statusobject.AbstractActuator (*args, **kwargs)`

Base class for all actuators.

**default = None**

Default value for status. For actuators, this is set by automatically created `DefaultProgram dp_actuatorname`

**slave = None**

If `True`, actual status can be set by any program anytime without restrictions.

**program = None**

A property giving current program governing the status of this actuator (program that has the highest priority)

**priorities = None**

This dictionary can be used to override program priorities.

---

**Note:** Keys here must be program names, (not `Program` instances).

---

**default\_program = None**

Reference to actuators `DefaultProgram`

**set\_status (status, origin=None, force=False)**

For programs, to set current status of the actuator. Each active program has its status in `program_stack` dictionary and the highest priority is realized in the actuator

**activate\_program (program)**

Called by program which desires to manipulate this actuator, when it is activated.

**deactivate\_program** (*program*)

Called by program, when it is deactivated.

**update\_program\_stack** ()

Update *program\_stack*. Used by programs *\_priority\_changed* attribute to reset ordering.

**get\_program\_status** (*prog*)

Give status defined by given program *prog*

**program\_stack = None**

Program stack of current programs, sorted automatically by program priority.

**program\_status = None**

Dictionary containing statuses set by each active program

## Builtin Statusobject Types

Here are the definitions for the builtin statusobject types (sensors and actuators). More types are available in *Extensions*.

### Builtin Sensors

Module for various Sensor classes.

**class** `automate.sensors.builtin_sensors.UserAnySensor` (*\*args, \*\*kwargs*)

User editable sensor type that accepts values of any types

**class** `automate.sensors.builtin_sensors.UserBoolSensor` (*\*args, \*\*kwargs*)

Boolean-valued user-editable sensor

**class** `automate.sensors.builtin_sensors.UserEventSensor` (*\*args, \*\*kwargs*)

Boolean-valued user-editable sensor suitable for using for singular events.

After status has been changed to `True`, it changes automatically its status back to `False`.

**class** `automate.sensors.builtin_sensors.AbstractNumericSensor` (*\*args, \*\*kwargs*)

Abstract class for numeric sensor types, that allows limiting value within a specific range.

If limiting values (*value\_min*, *value\_max*) are used, value that exceeds these limits, is clipped to the range.

**value\_min = None**

Minimum allowed value for status

**value\_max = None**

Maximum allowed value for status

**class** `automate.sensors.builtin_sensors.UserIntSensor` (*\*args, \*\*kwargs*)

Integer-valued user-editable sensor

**class** `automate.sensors.builtin_sensors.UserFloatSensor` (*\*args, \*\*kwargs*)

Float-valued user-editable sensor

**class** `automate.sensors.builtin_sensors.UserStrSensor` (*\*args, \*\*kwargs*)

String-valued user-editable sensor

**class** `automate.sensors.builtin_sensors.CronTimerSensor` (*\*args, \*\*kwargs*)

Scheduled start/stop timer. Both start and stop times are configured by cron-type string (see `man 5 crontab` for description of the definition format).

**timer\_on = None**

Semicolon separated lists of cron-compatible strings that indicate when to switch status to True

**timer\_off = None**

Semicolon separated lists of cron-compatible strings that indicate when to switch status to False

**class** `automate.sensors.builtin_sensors.FileChangeSensor (*args, **kwargs)`

Sensor that detects file changes on filesystem. Integer valued status is incremented by each change.

**filename = None**

Name of file or directory to monitor

**watch\_flags = None**

PyInotify flags to configure what file change events to monitor

**class** `automate.sensors.builtin_sensors.AbstractPollingSensor (*args, **kwargs)`

Abstract baseclass for sensor that polls periodically its status

**interval = None**

How often to do polling

**poll\_active = None**

This can be used to enable/disable polling

**class** `automate.sensors.builtin_sensors.PollingSensor (*args, **kwargs)`

Polling sensor that uses a Callable when setting the status of the sensor.

**status\_updater = None**

Return value of this Callable is used to set the status of the sensor when polling

**type = None**

If set, typeconversion to this is used. Can be any function or type.

**class** `automate.sensors.builtin_sensors.SimplePollingSensor (*args, **kwargs)`

Polling sensor that calls `on_update` periodically.

**class** `automate.sensors.builtin_sensors.IntervalTimerSensor (*args, **kwargs)`

Sensor that switches status between True and False periodically.

**class** `automate.sensors.builtin_sensors.SocketSensor (*args, **kwargs)`

Sensor that reads a TCP socket.

Over TCP port, it reads data per lines and tries to set the status of the sensor to the value specified by the line. If content of the line is 'close', then connection is dropped.

**host = None**

Hostname/IP to listen. Use '0.0.0.0' to listen all interfaces.

**port = None**

Port to listen

**stop = None**

set to True to tell SocketSensor to stop listening to port

**class** `automate.sensors.builtin_sensors.ShellSensor (*args, **kwargs)`

Run a shell command and follow its output. Status is set according to output, which is filtered through custome filter function.

**cmd = None**

Command can be, for example, 'tail -f logfile.log', which is convenient approach to follow log files.

**caller = None**

If this is set to true, caller object is passed to the filter function as second argument



**filter = None**

Filter function, which must be a generator, such as for example:

```
def filter(queue):
    while True:
        line = queue.get()
        if line == 'EOF':
            break
        yield line
```

or a simple line-by-line filter:

```
def filter(line):
    return processed(line)
```

## Builtin Actuators

Module for builtin Actuator classes

**class** `automate.actuators.builtin_actuators.BoolActuator(*args, **kwargs)`  
 Boolean valued actuator

**class** `automate.actuators.builtin_actuators.IntActuator(*args, **kwargs)`  
 Integer valued actuator

**class** `automate.actuators.builtin_actuators.FloatActuator(*args, **kwargs)`  
 Floating point valued actuator

**class** `automate.actuators.builtin_actuators.AbstractInterpolatingActuator(*args, **kwargs)`  
 Abstract base class for interpolating actuators.

**change\_frequency = None**  
 How often to update status (as frequency)

**slave\_actuator = None**  
 Slave actuator, that does the actual work (set `.slave` attribute to `True` in slave actuator)

**class** `automate.actuators.builtin_actuators.ConstantSpeedActuator(*args, **kwargs)`  
 Change slave status with constant speed

**speed = None**  
 Status change speed (change / second)

**class** `automate.actuators.builtin_actuators.ConstantTimeActuator(*args, **kwargs)`  
 Change slave status in constant time

**change\_time = None**  
 Time that is needed for change

## Callables

### Introduction

Callables are used like a small *programming language* to define the programming logic within the Automate system. All classes derived from *ProgrammableSystemObject* have five attributes that accept Callable type objects:

- Conditions
  - `active_condition`
  - `update_condition`
- Actions
  - `on_activate`
  - `on_update`
  - `on_deactivate`

Conditions determine *when* and actions, correspondingly, *what* to do.

Actions are triggered by *triggers* that are Sensors and Actuators. Triggers are collected from Callables (conditions and actions) automatically, and their status changes are subscribed and followed automatically by a `ProgrammableSystemObject`. Thus, condition statuses are evaluated automatically, and actions are executed based on condition statuses.

Let us take a look at a small example that uses conditions and actions:

```

from automate import *

class CounterClock(System):
    active_switch = UserBoolSensor()
    periodical = IntervalTimerSensor(interval=1)

    target_actuator = IntActuator()

    prog = Program(
        active_condition = Value(active_switch),
        on_activate = SetStatus(target_actuator, 0),
        on_update = SetStatus(target_actuator,
                             target_actuator + 1),
        triggers = [periodical],
        exclude_triggers = [target_actuator],
    )

s = CounterClock(services=[WebService(read_only=False)])
    
```

When user has switched `active_switch` sensor to `True`, this simple program will start adding `+1` to `target_actuator` value every second. Because `periodical` is not used as a trigger in any action/condition, we need to explicitly define it as a trigger with `triggers` attribute. Correspondingly, `target_actuator` is automatically collected as `prog`'s trigger (because it is the second argument of `SetStatus`), so we need to explicitly exclude it with `exclude_triggers` attribute.

---

**Tip:** Try the code yourself! Just paste the code into your IPython shell and go to <http://localhost:8080> in your browser! Screenshot:

ipython
New ▾ View ▾ Console Threads UML Log out

---

## Types view

Shows objects grouped by types

### Sensors

Name	Status
<b>IntervalTimerSensors</b>	
periodical	1.0
<b>UserBoolSensors</b>	
active_switch	<span style="border: 1px solid #ccc; padding: 2px;">True</span>

### Programs

Name	Pri	Act
prog	1	False

### Actuators

Name	Status
<b>IntActuator</b>	
target_actuator	42
prog	42.0
dp_target_actuator	0

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## Deriving Custom Callables

A collection of useful Callables is provided by `builtin_callables` module. It is also easy to derive custom callables from `AbstractCallable` baseclass. For most cases it is enough to re-define `call()` method.

If Callable utilizes threads (like `Delay`, `WaitUntil` and `While`) and continues as an background process after returning from call method, it is also necessary to define `cancel()` that notifies threads that their processing must be stopped. These threaded Callables can store their threads and other information in `state` dictionary, which stores information per caller Program. Per-caller state information is fetched via `get_state()`. After data is no longer needed, it must be cleared with `del_state()` method.

Arguments given to Callable are stored in `_args` and keyword arguments in `_kwargs`. There are the following shortcuts that may be used: `obj`, `value` and `objects`. When accessing these, it is necessary (almost) always to use `call_eval()` method, which evaluates concurrent status value out of Callable, StatusObject, or string that represents name of an object residing in System namespace. See more in the following section.

## Trigger and Target Collection

Triggers and targets are automatically collected from Callables recursively. All Callable types can specify which arguments are considered as triggers and which are considered as targets, by defining `_give_triggers()` and `_give_targets()`, correspondingly.

As a general rule, Callable should not consider criteria conditions as triggers (for example the conditions of `If`, `Switch` etc).

## Referring to Other Objects in Callables

Various system objects can be referred either by name (string), or by object references. Name is preferred, because it allows to refer to objects that are defined in different scopes (i.e. those that are defined either in `Groups` or later in the code).

If desired, automatic name referencing can be also disabled by setting `allow_name_referencing` `False`. Then it is possible to refer to other objects by using special construct `Object('name')`.

All variables passed to Callables are/must be evaluated through `call_eval()` method, i.e. if Callables are used as arguments, they are evaluated by their `call()` method and `StatusObject`'s status attribute is used, respectively.

## Callable Abstract Base Class definition

Callable classes are are subclassed of `AbstractCallable`.

**class** `automate.callable.AbstractCallable` (*\*args, \*\*kwargs*)

A base class for subclassing Callables that are used in Program conditions and action attributes.

Callables are configured by giving them arguments and keyword arguments. They must always define `call()` method which defines their functionality.

**triggers = None**

Property that gives set of all *triggers* of this callable and it's children callables. Triggers are all those `StatusObjects` that alter the status (return value of `call()`) of Callable.

**targets = None**

Property that gives set of all *targets* of this callable and it's children callables. Targets are all those `StatusObjects` of which status the callable might alter in `call()`.

**status = None**

Read-only status property of the callable. Usefull only when callable is used as a condition. This automatically depends on all the `StatusObjects` below the Callable tree.

**state = None**

State dictionary that is used by `call()` and `cancel()` if some state variables are needed to be saved. Remember to clean data in subclasses when it is no longer needed.

**get\_state** (*caller*)

Get per-program state.

**del\_state** (*caller*)

Delete per-program state.

**on\_setup\_callable = None**

Event that can be used to execute code right after callable setup. See *OfType*. Something that needs to be done manually this way, because Traits does not allow defining the order of subscribed function calls.

**call\_eval** (*value, caller, return\_value=True, \*\*kwargs*)

Value might be either name registered in System namespace, or object, either `StatusObject` or `Callable`. If `Callable`, evaluate `call()` method. If `StatusObject`, return status.

**setup\_callable\_system** (*system, init=False*)

This function basically sets up *system*, if it is not yet set up. After that, other Callable initialization actions are performed.

**Parameters** *init* – value `True` is given when running this at the initialization phase. Then *system* attribute is set already, but callable needs to be initialized otherwise.

**call** (*\*args, \*\*kwargs*)

The basic functionality of the Callable is implemented in this function. Needs to be defined in derived subclasses.

If callable is used as a Program condition, this must return the value of the condition (see for example conditions *And*, *Sum* etc.), otherwise return value is optional.

**objects**

Shortcut to `_args`.

**obj**

Shortcut property to the first stored object.

**value**

Shortcut property to the second stored object.

**name\_to\_system\_object** (*value*)

Return object for given name registered in System namespace.

**collect** (*target*)

Recursively collect all potential triggers/targets in this node and its children. Define targets and triggers of this particular callable in `_give_triggers()` and `_give_targets()`.

**Parameters** **target** (*str*) – valid values: 'targets' and 'triggers'

**children**

A property giving a generator that goes through all the children of this Callable (not recursive)

**\_give\_triggers** ()

Give all triggers of this object (non-recursive)

**\_give\_targets** ()

Give all targets of this object (non-recursive)

**cancel** (*caller*)

Recursively cancel all threaded background processes of this Callable. This is called automatically for actions if program deactivates.

**give\_str** ()

Give string representation of the callable.

**give\_str\_indented** (*tags=False*)

Give indented string representation of the callable. This is used in *Web User Interface for Automate*.

## Builtin Callables

Module `builtin_callables` provides classes that may be used to various purposes in Automate Program, in condition and action attributes. They are loaded automatically into `automate.callables` along with callables from possible installed extensions.

### Builtin Callable Types

**class** `automate.callables.builtin_callables.Empty` (*\*args, \*\*kwargs*)

Do nothing but return None. Default action in Programs.

Usage:

```
Empty ()
```

**class** `automate.callables.builtin_callables.AbstractAction` (*\*args, \*\*kwargs*)

Abstract base class for actions (i.e. callables that do something but do not necessarily return anything).

**class** `automate.callables.builtin_callables.Attrib` (*\*args, \*\*kwargs*)

Give specified attribute of a object.

**Parameters** `bool` (*no\_eval*) – if True, evaluation of object is skipped – use this to access attributes of SystemObjects

Usage & example:

```
Attrib(obj, 'attributename')
Attrib(sensor_name, 'status', no_eval=True)
```

**class** `automate.callables.builtin_callables.Method` (*\*args, \*\*kwargs*)  
Call method in an object with specified args

Usage:

```
Method(obj, 'methodname')
```

**class** `automate.callables.builtin_callables.Func` (*\*args, \*\*kwargs*)  
Call function with given arguments.

Usage & example:

```
Func(function, *args, **kwargs)
Func(time.sleep, 2)
```

**Parameters** `add_caller` (*bool*) – if True, then caller program is passed as first argument.

**class** `automate.callables.builtin_callables.OnlyTriggers` (*\*args, \*\*kwargs*)  
Baseclass for actions that do not have any targets (i.e. almost all actions).

**class** `automate.callables.builtin_callables.Log` (*\*args, \*\*kwargs*)  
Print callable argument outputs / other arguments to the log.

Usage:

```
Log(object1, object2, 'string1'...)
```

**Parameters** `log_level` (*str*) – Log level (i.e. logging function name) (default ‘info’)

**class** `automate.callables.builtin_callables.Debug` (*\*args, \*\*kwargs*)  
Same as *Log* but with debug logging level.

**class** `automate.callables.builtin_callables.ToStr` (*\*args, \*\*kwargs*)  
Return string representation of given arguments evaluated. Usage:

```
ToStr('formatstring {} {}', callable1, statusobject1)
```

**Parameters** `no_sub` (*bool*) – if True, removes format string from argument list. Then usage is simply:

```
ToStr(callable1, statusobject1, no_sub=True)
```

**class** `automate.callables.builtin_callables.Eval` (*\*args, \*\*kwargs*)  
Execute python command given as a string with eval (or exec).

Usage:

```
Eval("print time.{param}()", pre_exec="import time", param="time")
```

First argument: python command to be evaluated. If it can be evaluated by eval() then return value is the evaluated value. Otherwise, exec() is used and True is returned.

**Parameters**

- **pre\_exec** (*str*) – pre-execution string. For example necessary import commands.
- **namespace** (*dict*) – Namespace. Defaults to locals() in *builtin\_callables*.

Optionally, other keyword arguments can be given, and they are replaced in the first argument by format().

See also (and prefer using): *Func*

**class** automate.callables.builtin\_callables.**Exec** (\*args, \*\*kwargs)  
 Synonym to *Eval*

**class** automate.callables.builtin\_callables.**GetService** (\*args, \*\*kwargs)  
 Get service by name and number.

Usage:

```
GetService(name)
GetService(name, number)
```

Usage examples:

```
GetService('WebService')
GetService('WebService', 1)
```

**class** automate.callables.builtin\_callables.**ReloadService** (\*args, \*\*kwargs)  
 Reload given service.

Usage:

```
ReloadService(name, number)
ReloadService(name)
```

Usage examples:

```
ReloadService('WebService', 0)
ReloadService('ArduinoService')
```

**class** automate.callables.builtin\_callables.**Shell** (\*args, \*\*kwargs)  
 Execute shell command and return string value

**Parameters**

- **no\_wait** (*bool*) – if True, execute shell command in new thread and return pid
- **output** (*bool*) – if True, execute will return the output written to stdout by shell command. By default, execution status (integer) is returned.
- **input** (*str*) – if given, input is passed to stdin of the given shell command.

Usage examples:

```
Shell('/bin/echo test', output=True) # returns 'test'
Shell('mplayer something.mp3', no_wait=True) # returns PID of mplayer
                                                # process that keeps running
Shell('/bin/cat', input='test', output=True) # returns 'test'.
```

**class** automate.callables.builtin\_callables.**SetStatus** (\*args, \*\*kwargs)  
 Set sensor or actuator value

Usage:

```
SetStatus(target, source)
# sets status of target to the status of source.
SetStatus(target, source, Force=True)
# sets status to hardware level even if it is not changed
SetStatus([actuator1, actuator2], [sensor1, sensor2])
# sets status of actuator 1 to status of sensor1 and
# status of actuator2 to status of sensor2.
```

**class** `automate.callables.builtin_callables.SetAttr(*args, **kwargs)`  
 Set object's attributes

Usage:

```
SetAttr(obj, attr=value, attr2=value2)
# performs setattr(obj, attr, value) and setattr(obj, attr2, value2).
```

**class** `automate.callables.builtin_callables.Changed(*args, **kwargs)`  
 Is value changed since evaluated last time? If this is the first time this Callable is called (i.e. comparison to last value cannot be made), return True.

Usage:

```
Changed(sensor1)
```

**class** `automate.callables.builtin_callables.Swap(*args, **kwargs)`  
 Swap sensor or BinaryActuator status (False to True and True to False)

Usage:

```
Swap(actuator1)
```

**class** `automate.callables.builtin_callables.AbstractRunner(*args, **kwargs)`  
 Abstract baseclass for Callables that are used primarily to run other Actions

**class** `automate.callables.builtin_callables.Run(*args, **kwargs)`  
 Run specified Callables one at time. Return always True.

Usage:

```
Run(callable1, callable2, ...)
```

**class** `automate.callables.builtin_callables.Delay(*args, **kwargs)`  
 Execute commands delayed by time (in seconds) in separate thread

Usage:

```
Delay(delay_in_seconds, action)
```

**class** `automate.callables.builtin_callables.Threaded(*args, **kwargs)`  
 Execute commands in a single thread (in order)

Usage:

```
Threaded(action)
```

**class** `automate.callables.builtin_callables.If(*args, **kwargs)`  
 Basic If statement

Usage:



```
If(x, y, z) # if x, then run y, z, where x, y, and z are Callables or
↳StatusObjects
If(x, y)
```

**class** automate.callables.builtin\_callables.**IfElse**(\*args, \*\*kwargs)  
Basic if - then - else statement

Usage:

```
IfElse(x, y, z) # if x, then run y, else run z, where x, y,
# and z are Callables or StatusObjects
IfElse(x, y)
```

**class** automate.callables.builtin\_callables.**Switch**(\*args, \*\*kwargs)  
Basic switch - case statement.

Two alternative usages:

- First argument switch criterion (integer-valued) and others are cases **OR**
- First argument is switch criterion and second argument is dictionary that contains all possible cases as keys and related actions as their values.

Usage:

```
Switch(criterion, choice1, choice2...) # where criteria is integer-valued
# (Callable or StatusObject etc.)
# and choice1, 2... are Callables.

Switch(criterion, {'value1': callable1, 'value2': 'callable2'})
```

**class** automate.callables.builtin\_callables.**TryExcept**(\*args, \*\*kwargs)  
Try returning x, but if exception occurs in the value evaluation, then return y.

Usage:

```
Try(x, y) # where x and y are Callables or StatusObjects etc.
```

**class** automate.callables.builtin\_callables.**Integral**(\*args, \*\*kwargs)  
Calculate integral of object status within time interval

Usage:

```
Integral(sensor, time1, time2)
```

**class** automate.callables.builtin\_callables.**Min**(\*args, \*\*kwargs)  
Give minimum number of given objects.

Usage:

```
Min(x, y, z...)
# where x,y,z are anything that can be
# evaluated as number (Callables, Statusobjects etc).
```

**class** automate.callables.builtin\_callables.**Max**(\*args, \*\*kwargs)  
Give maximum number of given objects

Usage:

```
Max(x, y, z...)  
# where x,y,z are anything that can be  
# evaluated as number (Callables, Statusobjects etc).
```

**class** automate.callables.builtin\_callables.**Sum**(\*args, \*\*kwargs)  
Give sum of given objects

Usage:

```
Sum(x, y, z...)  
# where x,y,z are anything that can be  
# evaluated as number (Callables, Statusobjects etc).
```

**class** automate.callables.builtin\_callables.**Product**(\*args, \*\*kwargs)  
Give product of given objects

Usage:

```
Product(x, y, z...)  
# where x,y,z are anything that can be  
# evaluated as number (Callables, Statusobjects etc).
```

**class** automate.callables.builtin\_callables.**Mult**(\*args, \*\*kwargs)  
Synonym of Product

**class** automate.callables.builtin\_callables.**Division**(\*args, \*\*kwargs)  
Give division of given objects

Usage:

```
Division(x, y)  
# where x,y are anything that can be  
# evaluated as number (Callables, Statusobjects etc).
```

**class** automate.callables.builtin\_callables.**Div**(\*args, \*\*kwargs)  
Synonym of Division

**class** automate.callables.builtin\_callables.**Add**(\*args, \*\*kwargs)  
Synonym of Sum

**class** automate.callables.builtin\_callables.**AbstractLogical**(\*args, \*\*kwargs)  
Abstract class for logic operations (*And*, *Or* etc.)

**class** automate.callables.builtin\_callables.**Anything**(\*args, \*\*kwargs)  
Condition which gives *True* always

Usage:

```
Anything(x, y, z...)
```

**class** automate.callables.builtin\_callables.**Or**(\*args, \*\*kwargs)  
Or condition

Usage:

```
Or(x, y, z...) # gives truth value of x or y or z or ...
```

**class** automate.callables.builtin\_callables.**And**(\*args, \*\*kwargs)  
And condition

Usage:

```
And(x, y, z...) # gives truth value of x and y and z and ...
```

**class** automate.callables.builtin\_callables.**Neg** (\*args, \*\*kwargs)  
Give negative of specified callable (minus sign)

Usage:

```
Neg(x) # returns -x
```

**class** automate.callables.builtin\_callables.**Inverse** (\*args, \*\*kwargs)  
Give inverse of specified callable (1/something)

Usage:

```
Inv(x) # returns 1/x
```

**class** automate.callables.builtin\_callables.**Inv** (\*args, \*\*kwargs)  
Synonym of Inverse

**class** automate.callables.builtin\_callables.**Not** (\*args, \*\*kwargs)  
Give negation of specified object

Usage:

```
Not(x) # returns not x
```

**class** automate.callables.builtin\_callables.**Equal** (\*args, \*\*kwargs)  
Equality condition, i.e. is x == y

Usage:

```
Equal(x, y) # returns truth value of x == y
```

**class** automate.callables.builtin\_callables.**Less** (\*args, \*\*kwargs)  
Condition: is x < y

Usage:

```
Less(x, y) # returns truth value of x < y
```

**class** automate.callables.builtin\_callables.**More** (\*args, \*\*kwargs)  
Condition: is x > y

Usage:

```
More(x, y) # returns truth value of x > y
```

**class** automate.callables.builtin\_callables.**Value** (\*args, \*\*kwargs)  
Give specified value

Usage:

```
Value(x) # returns value of x. Used to convert StatusObject into Callable,  
# for example, if StatusObject status needs to be used directly  
# as a condition of Program condition attributes.
```

**class** automate.callables.builtin\_callables.**AbstractQuery** (\*args, \*\*kwargs)  
Baseclass for query type of Callables, i.e. those that return set of objects from system based on given conditions.

**class** `automate.callables.builtin_callables.OfType (*args, **kwargs)`  
Gives all objects of given type that are found in System

Usage & example:

```
OfType(type, **kwargs)
OfType(AbstractActuator, exclude=['actuator1', 'actuator2'])
# returns all actuators in system, except those named 'actuator1' and 'actuator2'.
```

**Parameters** `exclude (list)` – list of instances to be excluded from the returned list.

**class** `automate.callables.builtin_callables.RegexSearch (*args, **kwargs)`  
Scan through string looking for a match to the pattern. Return matched parts of string by `re.search()`.

**Parameters** `group (int)` – Match group can be chosen by group number.

Usage & examples:

```
RegexSearch(match_string, content_to_search, **kwargs)

RegexSearch(r'(\d*)(\w*)', '12test')           # returns '12'
RegexSearch(r'(\d*)(\w*)', '12test', group=2) # returns 'test'
RegexSearch(r'testasfd', 'test')              # returns ''
```

---

**Tip:** More examples in unit tests

---

**class** `automate.callables.builtin_callables.RegexMatch (*args, **kwargs)`  
Try to apply the pattern at the start of the string. Return matched parts of string by `re.match()`.

**Parameters** `group (int)` – Match group can be chosen by group number.

Usage & examples from unit tests:

```
RegexMatch(match_string, content_to_search, **kwargs)

RegexMatch(r'heptest', 'heptest')             # returns 'heptest'
RegexMatch(r'heptest1', 'heptest')           # returns ''
RegexMatch(r'(hep)te(st1)', 'heptest1', group=1) # returns 'hep'
RegexMatch(r'(hep)te(st1)', 'heptest1', group=2) # returns 'st1'
```

---

**Tip:** More examples in unit tests

---

**class** `automate.callables.builtin_callables.RemoteFunc (*args, **kwargs)`  
Evaluate remote function via XMLRPC.

Usage:

```
RemoteFunc('host', 'funcname', *args, **kwargs)
```

**class** `automate.callables.builtin_callables.WaitUntil (*args, **kwargs)`  
Wait until sensor/actuator/callable status changes to True and then execute commands. WaitUntil will return immediately and only execute specified actions after criteria is fulfilled.

Usage:

```
WaitUntil(sensor_or_callable, Action1, Action2, etc)
```

**Note:** No triggers are collected from WaitUntil

**class** `automate.callables.builtin_callables.While` (*\*args, \*\*kwargs*)  
 Executes commands (in thread) as long as criteria (sensor, actuator, callable status) remains true. Flushes worker queue between each iteration such that criteria is updated, if executed actions alter it.

**Parameters** `do_after` (*Callable*) – given Callable is executed after while loop is finished.

Usage & example:

```
While(criteria, action1, action2, do_after=action3)

# Example loop that runs actions 10 times. Assumes s=UserIntSensor()
Run (
    SetStatus(s, 0),
    While(s < 10,
        SetStatus(s, s+1),
        other_actions
    )
)
```

**Note:** While execution is performed in separate thread

**Note:** No triggers are collected from While

**class** `automate.callables.builtin_callables.TriggeredBy` (*\*args, \*\*kwargs*)  
 Return whether action was triggered by one of specified triggers or not

If no arguments, return the trigger.

Usage:

```
TriggeredBy() # -> returns the trigger
TriggeredBy(trig1, trig2...) #-> Returns if trigger is one of arguments
```

## Other Callable-like utilities

**class** `automate.tools.PushOver` (*name='', \*\*traits*)  
 Send push notifications to android/IOS phones (see <http://pushover.net>).

Use this as you would use a Callable.

**api\_key = None**  
 Pushover.net application/API token

**user\_key = None**  
 Pushover.net user key

**priority = None**  
 Pushover.net message priority

**device = None**  
Device name (empty to send to all devices)

**sound = None**  
Sound name in device

**class** `automate.tools.EmailSender` (*name=''*, *\*\*traits*)  
Send email notification of the current status of the system

**to\_email = None**  
Email address where email is to be sent

**smtp\_hostname = None**  
Smtp server

**smtp\_username = None**  
SMTP username

**smtp\_password = None**  
SMTP password

**smtp\_fromname = None**  
Name that appears in From: field

**smtp\_fromemail = None**  
Email that appears in From: field

## Automate System

### Introduction

`automate.system.System` encapsulates the state machine parts into single object. It has already been explained how to use System. Here we will go further into some details.

### Groups

In Automate system, it is possible to group objects by putting them to Groups. Grouping helps organizing objects in code level as well as in GUIs (*Web User Interface for Automate* etc.).

Here is an example:

```
class MySystem(System):
    class group1(Group):
        sensor1 = UserBoolSensor()
        sensor2 = UserBoolSensor()

    class group2(Group):
        sensor3 = UserBoolSensor()
        sensor4 = UserBoolSensor()
```

By adding SystemObject to a group, will assign it a tag corresponding to its groups class name. I.e. here, `sensor1` and `sensor2` will get tag `group:group1` and `sensor3` and `sensor4` will get tag `group:group2`.

System has single namespace dictionary that contains names of all objects. That implies that objects in different groups may not have same name.

## System State Saving and Restoring via Serialization

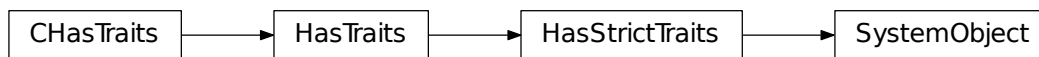
If System state is desired to be loaded later from periodically auto-saved state dumps, system can be instantiated via `load_or_create()` as follows:

```
my_system_instance = MySystem.load_or_create('my_statedump.dmp')
```

Then system state will be saved periodically (by default, once per 30 minutes) by `StatusSaverService`, which is automatically loaded service (see `Services`). If you desire to change interval, you need to explicitly define `dump_interval` as follows:

```
status_saver = StatusSaverService(dump_interval=10) # interval in seconds
my_system_instance = MySystem.load_or_create('my_statedump.dmp', services=[status_
↪saver])
```

## SystemObject



`SystemObject` is baseclass for all objects that may be used within `System` (most importantly, Sensors, Actuators and Programs).

Due to multiple inheritance, many `SystemObjects`, such as Sensors (`AbstractSensor`), Actuators (`AbstractActuator`), and Programs (`Program`) can act in *multiple roles*, in addition to their primary role, as follows:

- Sensors and actuators can always be used also as a program i.e. they may have conditions and action callables defined, because they derive from `ProgrammableSystemObject`.
- Both Actuators and Sensors can be used as *triggers* in Callables and via them in Programs
- Also plain Programs can be used as a Sensor. Then its activation status (boolean) serves as Sensor status.

Sensors and Programs do not have Actuator properties (i.e. per-program statuses), but Sensor status can still be set/written by a Program, similarly to actuators with `slave` attribute set to True.

## System Class Definition

```
class automate.system.System(loadstate=None, **traits)
```

```
    allow_name_referencing = None
```

```
        Allow referencing objects by their names in Callables. If disabled, you can still refer to objects by names by Object('name')
```

```
    filename = None
```

```
        Filename to where to dump the system state
```

```
    logfile = None
```

```
        Name of the file where logs are stored
```

**print\_level = None**  
Log level for the handler that writes to stdout

**logger = None**  
Reference to logger instance (read-only)

**raven\_dsn = None**  
Sentry: Raven DSN configuration (see <http://sentry.io>)

**log\_format = None**  
Format string of the log handler that writes to stdout

**logfile\_format = None**  
Format string of the log handler that writes to logfile

**log\_level = None**  
Log level of the handler that writes to logfile

**default\_services = None**  
Add here services that you want to be added automatically. This is meant to be re-defined in subclass.

**services = None**  
List of services that are loaded in the initialization of the System.

**exclude\_services = None**  
List of servicenames that are desired to be avoided (even if normally autoloaded).

**namespace = None**  
System namespace (read-only)

**objects\_sorted = None**  
Property giving objects sorted alphabetically (read-only)

**sensors = None**  
Read-only property giving all sensors of the system

**actuators = None**  
Read-only property giving all actuator of the system

**programs = None**  
Read-only property giving all objects that have program features in use

**ordinary\_programs = None**  
Read-only property giving all `Program` objects

**worker\_autostart = None**  
Start worker thread automatically after system is initialized

**pre\_exit\_trigger = None**  
Trigger which is triggered before quitting (used by `Services`)

**all\_tags = None**  
Read-only property that gives list of all object tags

**num\_state\_backups = None**  
Number of state backup files

**two\_phase\_queue = None**  
Enable experimental two-phase queue handling technique (not recommended)

**classmethod load\_or\_create** (*filename=None, no\_input=False, \*\*kwargs*)  
Load system from a dump, if dump file exists, or create a new system if it does not exist.



**save\_state()**  
 Save state of the system to a dump file `System.filename`

**cmd\_namespace**  
 A read-only property that gives the namespace of the system for evaluating commands.

**get\_unique\_name** (*obj*, *name=''*, *name\_from\_system=''*)  
 Give unique name for an Sensor/Program/Actuator object

**services\_by\_name**  
 A property that gives a dictionary that contains services as values and their names as keys.

**service\_names**  
 A property that gives the names of services as a list

**flush()**  
 Flush the worker queue. Usefull in unit tests.

**name\_to\_system\_object** (*name*)  
 Give SystemObject instance corresponding to the name

**eval\_in\_system\_namespace** (*exec\_str*)  
 Get Callable for specified string (for GUI-based editing)

**register\_service\_functions** (*\*funcs*)  
 Register function in the system namespace. Called by Services.

**register\_service** (*service*)  
 Register service into the system. Called by Services.

**request\_service** (*type*, *id=0*)  
 Used by Sensors/Actuators/other services that need to use other services for their operations.

**cleanup()**  
 Clean up before quitting

**cmd\_exec** (*cmd*)  
 Execute commands in automate namespace

**name = None**  
 Name of the system (shown in WEB UI for example)

**raven\_client = None**  
 Raven client (is created automatically if raven\_dsn is set and this is left empty)

**worker\_thread = None**  
 Reference to the worker thread (read-only)

**post\_init\_trigger = None**  
 Trigger which is triggered after initialization is ready (used by Services)

## SystemObjects Class Definition

```
class automate.systemobject.SystemObject (name='', **traits)
    Baseclass for Programs, Sensor, Actuators

    callables = []
        Names of attributes that accept Callables. If there are custom callables being used, they must
        be added here. The purpose of this list is that these Callables will be initialized properly.
        ProgrammableSystemObject introduces 5 basic callables (see also Programs).
```

**get\_default\_callables** ()

Get a dictionary of default callables, in form {name:callable}. Re-defined in subclasses.

**system** = None

Reference to System object

**description** = None

Description of the object (shown in WEB interface)

**tags** = None

Tags are used for (for example) grouping objects. See *Groups*.

**name** = None

Name property is determined by System namespace. Can be read/written.

**hide\_in\_uml** = None

If set to *True*, current SystemObject is hidden in the UML diagram of WEB interface.

**view** = ['hide\_in\_uml']

Attributes that can be edited by user in WEB interface

**data\_type** = ''

The data type name (as string) of the object. This is written in the initialization, and is used by WEB interface Django templates.

**editable** = False

If editable=True, a quick edit widget will appear in the web interface. Define in subclasses.

**object\_type**

A read-only property that gives the object type as string; sensor, actuator, program, other. Used by WEB interface templates.

**logger** = None

Python Logger instance for this object. System creates each object its own logger instance.

**get\_status\_display** (\*\*kwargs)

Redefine this in subclasses if status can be represented in human-readable way (units etc.)

**get\_as\_datadict** ()

Get information about this object as a dictionary. Used by WebSocket interface to pass some relevant information to client applications.

**setup** (\*args, \*\*kwargs)

Initialize necessary services etc. here. Define this in subclasses.

**setup\_system** (system, name\_from\_system='', \*\*kwargs)

Set system attribute and do some initialization. Used by System.

**setup\_callables** ()

Setup Callable attributes that belong to this object.

**cleanup** ()

Write here whatever cleanup actions are needed when object is no longer used.

## Services

### Introduction

There are two kinds of *Services* in Automate: *UserServices* and *SystemServices*.

*SystemServices* are mainly designed to implement a practical way of writing an interface between your custom SystemObjects and their corresponding resources (devices for example). For example, *RpioService* provide access to Raspberry Pi GPIO pins for *RpioActuator* and *RpioSensor* objects, and *ArduinoService*, correspondingly, provides access to Arduino devices for *ArduinoActuator* and *ArduinoSensors*. (Arduino and RPIO support are provided by extensions, see *Extensions*).

*UserServices*, on the other hand, provide user interfaces to the system. For example, *WebService* provides access to the system via web browser, *TextUIService* via *IPython* shell and *RpcService* via XmlRPC (remote procedure call) interface for other applications.

If not automatically loaded (services with *autoload* set to *True*), they need to be instantiated (contrary to *SystemObject*) outside the System, and given in the initialization of the system (*services*). For example of initialization and configuring of *WebService*, see “*Hello World*” in *Automate*.

## Services Class Definitions

**class** `automate.service.AbstractService`

Base class for System and UserServices

**autoload = False**

If set to *True*, service is loaded automatically (if not explicitly prevented in `automate.system.System.exclude_services`). Overwrite this in subclasses,

**setup ()**

Initialize service here. Define in subclasses.

**cleanup ()**

Cleanup actions must be performed here. This must be blocking until service is fully cleaned up.

Define in subclasses.

**class** `automate.service.AbstractUserService`

Baseclass for UserServices. These are set up on startup. They provide usually user interaction services.

**class** `automate.service.AbstractSystemService`

Baseclass for SystemServices. These are set up by when first requested by Sensor or other object.

## Builtin Services

**class** `automate.services.logstore.LogStoreService`

Provides interface to log output. Used by WebService.

**log\_level = None**

Log level

**log\_length = None**

Log length

**most\_recent\_line = None**

The most recent log line is always updated here. t Subscription to this attribute can be used to follow new log entries.

**class** `automate.services.statussaver.StatusSaverService`

Service which is responsible for scheduling dumping system into file periodically.

**dump\_interval = None**

Dump saving interval, in seconds. Default 30 minutes.

**class** `automate.services.plantuml.serv.PlantUMLService`

Provides UML diagrams of the system as SVG images. Used by WebService.

PLantUMLService requires either PlantUML software (which is opensource software written in Java) to be installed locally (see <http://plantuml.sourceforge.net/>) or it is possible to use online service of plantuml.com In addition you need python package `plantuml` (available via PYPI).

**url = None**

URL of PlantUML Java Service. To use PlantUML online service, set this to `'http://www.plantuml.com/plantuml/svg/'`

**arrow\_colors = None**

Arrow colors as HTML codes stored as a dictionary with keys: `controlled_target`, `active_target`, `inactive_target`, `trigger`

**background\_colors = None**

Background colors as HTML codes, stored as a dictionary with keys: `program`, `actuator`, `sensor`

**write\_puml** (*filename=''*)

Writes PUML from the system. If filename is given, stores result in the file. Otherwise returns result as a string.

**write\_svg** ()

Returns PUML from the system as a SVG image. Requires `plantuml` library.

**class** `automate.services.textui.TextUIService`

Provides interactive Python shell frontend to the System. Uses IPython if it is installed. Provides couple of functions to the System namespace.

**ls** (*what*)

List actuators, programs or sensors (what is string)

**lsa** ()

List actuators

**lsp** ()

List programs

**lss** ()

List sensors

**help** (*\*args, \*\*kwargs*)

Print Automate help if no parameter is given. Otherwise, act as `pydoc.help()`

**text\_ui** ()

Start Text UI main loop

## Extensions

Automate functionality can be easily extended by various extension modules, and it is also possible to make your own Automate extensions, for details see *Making your own Automate Extensions*. The following extensions are included in Automate:

### Web User Interface for Automate

## Introduction

Automate Web UI extension provides easy to use approach to monitoring and modifying Automate system and its components. Features:

- Displayed data updated in real time via Websocket
- Responsive design (using [Bootstrap](#) CSS & JS library), suitable for mobile and desktop use.
- Optional authentication
- Read-only and read-write modes.
  - Read-only mode allows only monitoring (default)
  - Read-write mode allows modifying the System by:
    - \* adding new Actuators / Sensors / Programs
    - \* modifying existing Actuators / Sensors / Programs
    - \* Quick editing of user-editable sensors from main views
- HTTP and secured HTTPS servers supported (powered by built in Tornado Web Server)

Main features are illustrated with a few screenshots:

## Installation

Install extras:

```
pip install automate[web]
```

## Main view

In main view you can observe actuator and sensor statuses in real time, and also easily access user-editable sensor statuses. Clicking object name will give more details of the selected item as well as 'edit' button. (only in read-write mode).

## Edit view

In edit view you can edit almost all the attributes of the objects that are in the system. You can also create new ones.

## UML view

In UML view you can see nice UML diagram of the whole system. To enable UML diagram, you need to set up `PlantUMLService`.

## Console view

In console view you can see the log as well as type commands same way as in IPython shell.

autoaqua New ▾ View ▾ Tags ▾ Custom ▾ Log out

## Tag view

Shows objects grouped by tags

### group:Ajastimet

- 📊 📈 co2\_ajastin False
- 📊 📈 co2\_ajastin\_loma True
- 📊 📈 lamput\_ajastin True
- 📊 📈 lamppu1\_ajastin False
- 📊 📈 lamppu2\_ajastin True
- 📊 📈 lamppu3\_ajastin True
- 📊 📈 dimmer\_ajastin False
- 📊 📈 lamput\_ajastin\_loma True
- 📊 📈 ajastinohjelma True

### group:SystemInfo

- 📊 📈 load\_average 0.4

Graph

- 📊 📈 memory 50.6

Info for memory Edit

Interval	10.0
Class name	PollingSensor
Data type	NoneType
Integral	3366.016181254387
Average	42.783959108992335

### holiday

- 📊 📈 co2\_ajastin\_loma True
- 📊 📈 lamput\_ajastin\_loma True

### quick

- 📊 📈 vesivahinko\_kytkin False

Info for vesivahinko\_kytkin Edit

Default	0
Class name	UserBoolSensor
Data type	bool
Integral	0.0
Average	0.0

Program features

**Priority** 1.0

**On activate**

`Empty()`

**On deactivate**

`setStatus('silence_alarm', 0)`

**On update**

`Empty()`

**Active condition**

`Value('vesivahinko_kytkin')`

**Update condition**

`Value(True)`

### group:Alarm

- 📊 📈 alarminterval 0.0
- 📊 📈 silence\_alarm False
- 📊 📈 alarm False
- 📊 📈 alarmtrigger False

### group:Vesiaktuaattorit

- 📊 📈 uvc True
- 📊 📈 pumput True
- 📊 📈 co2 True
- 📊 📈 lammitin True

### group:Kytkimet



## Log console

```

16:42:13 autoaqua.TextUIService working model.
16:42:13 autoaqua.TextUIService
16:42:13 autoaqua.TextUIService Any Python commands are accepted. You may refer to all your
16:42:13 autoaqua.TextUIService automate objects by their name attribute. You may do anything to
16:42:13 autoaqua.TextUIService modify the state on fly by this field, for example, create new programs,
16:42:13 autoaqua.TextUIService actuators, sensors, etc. Some practical commands:
16:42:13 autoaqua.TextUIService
16:42:13 autoaqua.TextUIService help -- show this help message (or with parameter, normal pydoc)
16:42:13 autoaqua.TextUIService lsa, lsp, lss -- list actuators, programs, sensors
16:42:13 autoaqua.TextUIService get_statusmsg -- print current system status
16:42:13 autoaqua.TextUIService gui -- show GUI
16:42:13 autoaqua.TextUIService quit -- quit cleanly
16:42:13 autoaqua.TextUIService
16:42:13 autoaqua.TextUIService python_str(filename) -- print all objects in a python file
16:42:13 autoaqua.TextUIService obj.set_value(value) -- set object value for obj
16:42:13 autoaqua.TextUIService obj.print_traits() -- print all traits attributes for obj
16:42:13 autoaqua.TextUIService
16:42:13 autoaqua.RelayActuator.lamppul RelayActuator lamppul (by lampul) setting status to True
16:42:42 autoaqua.RelayActuator.uvc RelayActuator uvc (by ajastinchjelma) setting status to True
16:43:39 autoaqua.WebService WebSocket opened for session d8nx9ydo5zl3msneyqe7jtw25pb0ctm2
16:44:13 autoaqua.RelayActuator.lamppu3 RelayActuator lamppu3 (by lampul) setting status to True
16:44:25 autoaqua.UserBoolSensor.valot_manuaalimoodi status changed to True
16:44:25 autoaqua.BoolActuator.lampul BoolActuator lampul (by valot_manuaalimoodi) setting status to False
16:44:25 autoaqua.RelayActuator.lamppul RelayActuator lamppul (by lampul) setting status to False
16:44:54 autoaqua.WebService WebSocket closed for session d8nx9ydo5zl3msneyqe7jtw25pb0ctm2
16:44:54 autoaqua.WebService WebSocket opened for session d8nx9ydo5zl3msneyqe7jtw25pb0ctm2

```

Command  Run

[Switch to multiine](#)

## Example application using Web UI

This is extended example of the “Hello World” in Automate, that opens two web services, one for port 8085 and another in 8086. It will go to UML view by default and in “User defined” -view you will see only web\_switch.

```

from automate import *

class MySystem(System):
    # HW swtich connected Raspberry Pi GPIO port 1
    hardware_switch = RpioSensor(port=1)
    # Switch that is controllable, for example, from WEB interface
    web_switch = UserBoolSensor(tags=['user'])
    # Lamp relay that switches lamp on/off, connected to GPIO port 2
    lamp = RpioActuator(port=2)
    # Program that controls the system behaviour
    program = Program(
        active_condition = Or('web_switch', 'hardware_switch'),
        on_activate = SetStatus('lamp', True)
    )

# To view UML diagram, we need to set up PlantUMLService. Here we will use
# plantuml.com online service to render the UML graphics.
plantuml_service = PlantUMLService(url='http://www.plantuml.com/plantuml/svg/')
web_service = WebService(
    read_only=False,
    default_view='plantuml',
    http_port=8085,
    http_auth = ('myusername', 'mypassword'),
    user_tags = ['user'],

```



```

        )

# Just to give example of slave feature, let's open another server instance
# at port 8086.
slave = Webservice(
    http_port=8086,
    slave=True,
)

my_system = MySystem(services=[plantuml_service, web_service, slave])

```

**Tip:** Try to run the code in your IPython shell by copying & pasting it with `cpaste` command!

## WebService class definition

**class** `automate.extensions.webui.WebService`

Web User Interface Service for Automate

**read\_only = None**

Restrict usage to only monitoring statuses (default: `True`). If `WebService` is not in `read_only` mode, it is possible to run arbitrary Python commands through `eval/exec` via web browser. This is, of course, a severe security issue. Secure SSL configuration **HIGHLY** recommended, if not operating in `read_only` mode.

**default\_view = None**

Default view that is displayed when entering the server. Can be the name of any view in `views.py`

**http\_port = None**

HTTP port to listen

**http\_auth = None**

Authentication for logging into web server. (user,password) pairs in a tuple.

**websocket\_timeout = None**

Let websocket connection die after `websocket_timeout` time of no ping reply from client.

**user\_tags = None**

Tags that are shown in user defined view

**debug = None**

Django debugging mode (slower, more info shown when error occurs)

**custom\_pages = None**

User-defined custom pages as a dictionary of form `{name: template_content}`

**slave = None**

set to `True`, if you want to launch multiple servers with same system. Authentication and other settings are then taken from master service. Only web server settings (http host/port) are used from slave.

**django\_settings = None**

In this dictionary you can define your custom Django settings which will override the default ones

**redirect\_from\_setters = None**

From `/set/object/value` and `/toggle/object`, redirect to `/set_ready/object/value` after after executing action

**show\_hidden = None**

Show hidden objects in web UI (those prefixed with `_`)

**server\_url = None**  
Full exposed url root

## WSGI Support for Automate

This extension provides Web server for WSGI-aware extensions, such as *Remote Procedure Call Support for Automate*, *Web User Interface for Automate*. It is of no use alone.

### Class definition

**class** `automate.extensions.wsgi.TornadoService`  
Abstract service that provides HTTP server for WSGI applications.

**http\_ipaddr = None**  
Which ip address to listen. Use `0.0.0.0` (default) to listen to all local networking interfaces.

**http\_port = None**  
HTTP (or HTTPS if using SSL) port to listen

**ssl\_certificate = None**  
Path to ssl certificate file. If set, SSL will be used.

---

**Tip:** You may use script `scripts/generate_selfsigned_certificate.sh` to generate a self-signed openssl certificate.

---

**ssl\_private\_key = None**  
Path to ssl private key file

**num\_threads = None**  
Number of listener threads to spawn

**static\_dirs = None**  
Extra static dirs you want to serve. Example:

```
static_dirs = {'/my_static/(.*)': '/path/to/my_static'}
```

**get\_wsgi\_application()**  
Get WSGI function. Implement this in subclasses.

## Remote Procedure Call Support for Automate

### Introduction

This extension provides XmlRPC API for external applications. Exported API is by default defined by `automate.extensions.rpc.rpc.ExternalApi`.

### Installation

Install extras:

```
pip install automate[rpc]
```

## Class definitions

**class** `automate.extensions.rpc.RpcService`

**view\_tags = None**

Tags that are displayed via `get_websensors` RPC function

**api = None**

If you want to define custom api (similar to, or derived from `ExternalApi`, it can be given here.

**class** `automate.extensions.rpc.rpc.ExternalApi` (*system, tag*)

**set\_status** (*name, status*)

Set sensor name status to *status*.

**get\_status** (*name*)

Get status of object with name *name*.

**set\_object\_status** (*statusdict*)

Set statuses from a dictionary of format `{name: status}`

**toggle\_object\_status** (*objname*)

Toggle boolean-valued sensor status between `True` and `False`.

**get\_sensors** ()

Get sensors as a dictionary of format `{name: status}`

**get\_websensors** ()

Get sensors with defined tag as a dictionary of format `{name: status}`

**get\_actuators** ()

Get actuators as a dictionary of format `{name: status}`

**flush** ()

Flush the system queue. If you have just set a status and then read a value, it might be necessary to flush queue first, such that related changes have been applied.

**is\_alive** ()

Simple RPC command that returns always `True`.

**log** ()

Return recent log entries as a string.

## Arduino Support for Automate

### Introduction

This extension provides interface to Arduino devices via [pyFirmata library](#). You can use either `StandardFirmata` or preferably `AutomateFirmata`, which offers additional features that can be used with Automate. Please use corresponding version of `AutomateFirmata` from [releases -page](#). I have tested this module with Arduino Pro Mini compatible boards but it should work with others too.

### Example application

This example application sets up couple of analog and digital Arduino Sensors and Actuators. It also introduces Servo actuator with `ConstantTimeActuator`, which functions such a way that if value of `a1` changes, the value of `servo` will change smoothly within given time interval.

```

from automate import *

class MySystem(System):
    ufloat = UserFloatSensor(value_min=0, value_max=1)

    a1 = ArduinoAnalogSensor(service=0, pin=0)
    d12 = ArduinoDigitalSensor(service=0, pin=12)

    d13 = ArduinoDigitalActuator(service=0, pin=13) # LED on Arduino board
    pwm = ArduinoPWMActuator(service=0, pin=4, on_update=SetStatus('pwm', 'ufloat'))
    servo = ArduinoServoActuator(min_pulse=200,
                                 max_pulse=8000,
                                 service=0,
                                 pin=3,
                                 default=50,
                                 slave=True)

    interp = ConstantTimeActuator(change_time=2.,
                                   change_frequency=20.,
                                   slave_actuator=servo)

    prog = Program(
        on_update=Run(Log("Value: %s", Value(a1)),
                      SetStatus(d13, d12),
                      SetStatus(interp, Value(180) * Value(a1)))
    )

my_arduino = ArduinoService(
    device="/dev/ttyUSB0",
    sample_rate=500,
)

s = MySystem(services=[my_arduino, Webservice()])

```

## VirtualWire wireless communication

VirtualWire enables communication between two Arduinos with very cheap radio frequency (RF) transmitters&receivers. For more information about VirtualWire, see for example [this link](#). It is possible to make Automate communicate with remote Arduinos via VirtualWire. How to do this:

To configure independent Arduino transmitter module with Automate:

1. Flash AutomateFirmata to your Arduino
2. Make simple Automate application to configure Arduino that configures which pin values you are interested in being transmitted via VirtualWire, something like this:

```

class ArduinoSystem(System):
    digital_sensor1 = ArduinoDigitalSensor(pull_up_resistor=True, pin=2)
    digital_sensor2 = ArduinoDigitalSensor(pull_up_resistor=True, pin=3)
    analog_sensor1 = ArduinoAnalogSensor(pin=0)
    analog_sensor2 = ArduinoAnalogSensor(pin=1)

s = ArduinoSystem(
    services=[
        ArduinoService(

```

```

        device="/dev/ttyUSB0",
        sample_rate=2000,
        home_address=1,
        device_address=1,
        virtualwire_tx_pin=11,
        virtualwire_ptt_pin=12,
    ),
    ],
)

```

Here you need to connect your RF transmitter device to digital pin 11. With some transmitter devices you might save some power by using push to talk (PTT) pin 12 to power on/off your transmitter device. This will configure your module to transmit values from analog pins 0 and 1, and digital pins 2 and 3. Now you can disconnect Arduino's serial interface and it will work independently. When running this configuration application, Arduino stores configuration to its EEPROM memory, such that after booting you don't need any more configuration. AutomateFirmata also saves power when in transmitter mode, so you can implement battery powered sensors that consume very little battery.

To listen these events, you need another Arduino that is connected permanently to your Automate computer:

```

class ArduinoSystem(System):
    digi1 = ArduinoRemoteDigitalSensor(device=1, pin=2)
    digi2 = ArduinoRemoteDigitalSensor(device=1, pin=3)
    analog1 = ArduinoRemoteAnalogSensor(device=1, pin=0)
    analog2 = ArduinoRemoteAnalogSensor(device=1, pin=1)

s = ArduinoSystem(
    services=[
        ArduinoService(
            device="/dev/ttyUSB0",
            sample_rate=2000,
            home_address=1,
            device_address=2,
            virtualwire_rx_pin=10,
        ),
    ],
)

```

Notice that here you need to configure `device` attribute same as `device_address` that you configured above. Also `home_address` needs to be same between all Arduino devices that you configure in your system.

You can also configure independent receiver module:

```

s = System(
    services=[
        ArduinoService(
            device="/dev/ttyUSB0",
            sample_rate=2000,
            home_address=1,
            device_address=3,
            virtualwire_rx_pin=11,
        ),
    ],
)

```

This is all that is needed for receiver. What this does is sets `home_address`, `device_address` and `virtualwire_tx_pin` in your Arduino receiver device correctly. You must connect your RF receiver device to digital pin 11. Now you can control this device remotely like this:

```

class ArduinoSystem(System):
    ubool = UserBoolSensor()
    ufloat1 = UserFloatSensor(value_min=0, value_max=1)

    remote_actuator = ArduinoRemoteDigitalActuator(
        device=3, pin=13,
        on_update=SetStatus('remote_actuator', 'ubool'))

    remote_pwm = ArduinoRemotePWMActuator(
        device=3, pin=5,
        on_update=SetStatus('remote_pwm', 'ufloat1'))

s = ArduinoSystem(
    services=[
        ArduinoService(
            device="/dev/ttyUSB0",
            sample_rate=2000,
            home_address=1,
            device_address=4,
            virtualwire_tx_pin=11,
            virtualwire_ptt_pin=12,
        ),
        Webservice(read_only=False),
    ],
)

```

Here, you must configure your RF transmitter to digital pin 11.

## Class definitions

### Service

**class** `automate.extensions.arduino.ArduinoService` (\*args, \*\*kwargs)

Service that provides interface to Arduino devices via `pyFirmata` library.

**device = None**

Arduino devices to use, as a list

**device\_type = None**

Arduino device board type, choices: 'arduino', 'arduino\_mega', 'arduino\_due'.

**sample\_rate = None**

Arduino sample rate in milliseconds (i.e. how often to send data to host)

**home\_address = None**

Device home address (0-255) in VirtualWire network. This should be same for all devices in a network.

**device\_address = None**

Device address (0-255) in VirtualWire network. Unique for each device.

**virtualwire\_tx\_pin = None**

VirtualWire transfer pin

**virtualwire\_rx\_pin = None**

VirtualWire receiver pin

**virtualwire\_ptt\_pin = None**  
VirtualWire PTT (push to talk) pin

**lcd\_port = None**  
LCD Port

**lcd\_columns = 16**  
LCD Columns

**lcd\_rows = 2**  
LCD Rows

**wakeup\_pin = None**  
Wakeup pin (0 to disable) that wakes Arduino from sleep mode. On Atmega328 based boards, possible values are 2 and 3

**virtualwire\_speed = None**  
VirtualWire speed, (bit rate = speed \* 1000 bps). Values 1-9 are allowed. Values up to 7 should be working, but your mileage may vary.

**keep\_alive = None**  
Send keep-alive messages periodically over serial port to prevent Arduino device from falling to power save mode.

**change\_digital** (*pin\_nr, value*)  
Change digital Pin value (boolean). Also PWM supported(float)

## Sensors

**class** `automate.extensions.arduino.arduino_sensors.AbstractArduinoSensor` (*\*args, \*\*kwargs*)

Abstract base class for Arduino sensors

**service = None**  
Arduino service number (specify, if more than 1 ArduinoServices are configured in system)

**pin = None**  
Arduino pin number

**class** `automate.extensions.arduino.arduino_sensors.ArduinoDigitalSensor` (*\*args, \*\*kwargs*)

Boolean-valued sensor object for digital Arduino input pins

**pull\_up\_resistor = None**  
Enable built-in pull-up resistor

**inverted = None**  
Set to True to have inversed status value

**class** `automate.extensions.arduino.arduino_sensors.ArduinoAnalogSensor` (*\*args, \*\*kwargs*)

Float-valued sensor object for analog Arduino input pins

**class** `automate.extensions.arduino.arduino_sensors.ArduinoRemoteDigitalSensor` (*\*args, \*\*kwargs*)

Sensor which listens to status changes of remote digital input pin (transmission via VirtualWire).

Needs [AutomateFirmata](#)

**device = None**  
Source device number

**inverted = None**

Set to True to have inversed status value

**class** `automate.extensions.arduino.arduino_sensors.ArduinoRemoteAnalogSensor` (*\*args*,  
*\*\*kwargs*)

Sensor which listens to status changes of remote analog input pin (transmission via VirtualWire)

Needs [AutomateFirmata](#)

**device = None**

Source device number

## Actuators

**class** `automate.extensions.arduino.arduino_actuators.AbstractArduinoActuator` (*\*args*,  
*\*\*kwargs*)

Abstract base class for Arduino actuators

**service = None**

Arduino service number (specify, if more than 1 ArduinoService are configured in the system)

**pin = None**

Arduino pin number

**class** `automate.extensions.arduino.arduino_actuators.ArduinoDigitalActuator` (*\*args*,  
*\*\*kwargs*)

Boolean-valued actuator object for digital Arduino output pins

**class** `automate.extensions.arduino.arduino_actuators.ArduinoLCDActuator` (*\*args*,  
*\*\*kwargs*)

Actuator that sends target device digital output pin status change requests

Needs [AutomateFirmata](#)

**device = None**

Target device number

**class** `automate.extensions.arduino.arduino_actuators.ArduinoRemoteDigitalActuator` (*\*args*,  
*\*\*kwargs*)

Actuator that sends target device digital output pin status change requests

Needs [AutomateFirmata](#)

**device = None**

Target device number

**class** `automate.extensions.arduino.arduino_actuators.ArduinoRemotePWMActuator` (*\*args*,  
*\*\*kwargs*)

Actuator that sends target device analog (PWM) output pin status change requests

Needs [AutomateFirmata](#)

**device = None**

Target device number

**class** `automate.extensions.arduino.arduino_actuators.ArduinoServoActuator` (*\*args*,  
*\*\*kwargs*)

Float-valued actuator object for Arduino output pins that can be configured in Servo mode Status is servo angle (0-360).

**min\_pulse = None**

Minimum pulse time (in microseconds)



**max\_pulse = None**  
Maximum pulse time (in microseconds)

**class** automate.extensions.arduino.arduino\_actuators.**ArduinoPWMActuator** (\*args, \*\*kwargs)  
Float-valued actuator object for Arduino output pins that can be configured in PWM mode Status is float between 0.0 and 1.0.

## Raspberry Pi GPIO Support for Automate

### Introduction

This extension provides interface to Raspberry Pi GPIO via RPIO library. [RPIO library](#).

### Installation

Install extras:

```
pip install automate[raspberrypi]
```

### Example application

This simple example application sets up simple relation between input pin `button` in port 22 and output pin `light` in port 23. If for a button is attached in `button`, pushing it down will light the led, that is attached to `light`.

```
from automate import *
from automate.extensions.rpio import RpioSensor, RpioActuator

class MySystem(System):
    button = RpioSensor(port=22, button_type='down')
    light = RpioActuator(port=23, change_delay=2)
    myprog = Program(active_condition=Value('mysensor'),
                     on_activate=SetStatus('myactuator', True))

mysystem = MySystem()
```

### Class definitions

#### Service

**class** automate.extensions.rpio.**RpioService**  
Service that provides interface to Raspberry Pi GPIO via [RPIO library](#).

**gpio\_cleanup = None**  
Perform GPIO cleanup when exiting (default: False).

**rpio = None**  
Use RPIO instead of RPI.GPIO

## Sensors

**class** `automate.extensions.rpio.RpioSensor (*args, **kwargs)`  
 Boolean-valued sensor object that reads Raspberry Pi GPIO input pins.

**port = None**  
 GPIO port

**inverted = None**  
 Set to True to have inversed status value

**button\_type = None**  
 Button setup: “down”: pushdown resistor, “up”: pushup resistor, or “none”: no resistor set up.

**class** `automate.extensions.rpio.RpioSensor (*args, **kwargs)`  
 Boolean-valued sensor object that reads Raspberry Pi GPIO input pins.

**port = None**  
 GPIO port

**inverted = None**  
 Set to True to have inversed status value

**button\_type = None**  
 Button setup: “down”: pushdown resistor, “up”: pushup resistor, or “none”: no resistor set up.

## Actuators

**class** `automate.extensions.rpio.RpioActuator (*args, **kwargs)`  
 Boolean-valued actuator for setting Raspberry Pi GPIO port statuses (on/off).

**port = None**  
 GPIO port id

**inverted = None**  
 Set to True to have inversed status value

**class** `automate.extensions.rpio.TemperatureSensor (*args, **kwargs)`  
 W1 interface (on Raspberry Pi board) that polls polling temperature. (kernel modules w1-gpio and w1-therm required). Not using RPIO, but placed this here, since this is also Raspberry Pi related sensor.

**addr = None**  
 Address of W1 temperature sensor (something like "28-00000558263c"), see what you have in /  
 sys/bus/w1/devices/

**max\_jump = None**  
 Maximum jump in temperature, between measurements. These temperature sensors tend to give some-  
 times erroneous results.

**max\_errors = None**  
 Maximum number of erroneous measurements, until value is really set

**class** `automate.extensions.rpio.RpioPWMActuator (*args, **kwargs)`  
 Actuator to control PWM (pulse-width-modulation) ports on Raspberry pi GPIO.

Status range 0...1

This is not recommended to be used because RPIO PWM implementation is not very well behaving. I recom-  
 mend to use ArduinoPWMActuator with an Arduino loaded with StandardFirmata. It’s much more stable and  
 robust solution.

**port = None**  
GPIO port number

**dma\_channel = None**  
RPIO PWM DMA channel

**frequency = None**  
PWM frequency (Hz)

## Making your own Automate Extensions

### Extension Development

Automate extensions allow extending Automate functionalities by writing external libraries that may consist of new Service, Sensor, Actuator, or Callable classes.

To start developing automate extensions, it is recommended to use [cookiecutter](#) template. This is how it works:

1. Install `cookiecutter` 1.0.0 or newer:

```
pip install cookiecutter
```

2. Generate a Automate extension project:

```
cookiecutter https://github.com/tuomas2/cookiecutter-automate-ext-template.git
```

Cookiecutter asks few questions and you have great basis for starting your template development. There will be created Python files where you may add your new custom Automate classes.

For your classes to be exported to the Automate, make sure that they are listed in `extension_classes` list in `__init__.py` of the extension module.

All installed Automate Extensions are available from Automate applications and are imported to `automate` namespace.

---

**Tip:** You can install your extension in *editable* mode by running `pip install -e .` in your extension root directory.

---

**Tip:** You can look at *Extensions* for examples.

---

- `genindex`



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