
MicroPython Documentation

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Damien P. George and contributors

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QUICK REFERENCE FOR THE WIPY

1.1 General board control (including sleep modes)

See the `machine` module:

```
import machine

help(machine) # display all members from the machine module
machine.freq() # get the CPU frequency
machine.unique_id() # return the 6-byte unique id of the board (the WiPy's MAC address)

machine.idle()      # average current decreases to (~12mA), any interrupts wake it up
machine.sleep()    # everything except for WLAN is powered down (~950uA avg. current)
                  # wakes from Pin, RTC or WLAN
machine.deepsleep() # deepest sleep mode, MCU starts from reset. Wakes from Pin and RTC.
```

1.2 Pins and GPIO

See `machine.Pin`.

```
from machine import Pin

# initialize GP2 in gpio mode (alt=0) and make it an output
p_out = Pin('GP2', mode=Pin.OUT)
p_out.value(1)
p_out.value(0)
p_out.toggle()
p_out(True)

# make GP1 an input with the pull-up enabled
p_in = Pin('GP1', mode=Pin.IN, pull=Pin.PULL_UP)
p_in() # get value, 0 or 1
```

1.3 Timers

See `machine.Timer` and `machine.Pin`.

```
from machine import Timer
from machine import Pin
```

```
tim = Timer(0, mode=Timer.PERIODIC)
tim_a = tim.channel(Timer.A, freq=1000)
tim_a.time() # get the value in microseconds
tim_a.freq(5) # 5 Hz

p_out = Pin('GP2', mode=Pin.OUT)
tim_a.irq(handler=lambda t: p_out.toggle())
```

1.4 PWM (pulse width modulation)

See `machine.Pin` and `machine.Timer`.

```
from machine import Timer

# timer 1 in PWM mode and width must be 16 bits
tim = Timer(1, mode=Timer.PWM, width=16)

# enable channel A @1KHz with a 50.55% duty cycle
tim_a = tim.channel(Timer.A, freq=1000, duty_cycle=5055)
```

1.5 ADC (analog to digital conversion)

See `machine.ADC`.

```
from machine import ADC

adc = ADC()
apin = adc.channel(pin='GP3')
apin() # read value, 0-4095
```

1.6 UART (serial bus)

See `machine.UART`.

```
from machine import UART

uart = UART(0, baudrate=9600)
uart.write('hello')
uart.read(5) # read up to 5 bytes
```

1.7 SPI bus

See `machine.SPI`.

```
from machine import SPI

# configure the SPI master @ 2MHz
spi = SPI(0, SPI.MASTER, baudrate=200000, polarity=0, phase=0)
spi.write('hello')
spi.read(5) # receive 5 bytes on the bus
```

```
rbuf = bytearray(5)
spi.write_readinto('hello', rbuf) # send a receive 5 bytes
```

1.8 I2C bus

See `machine.I2C`.

```
from machine import I2C
# configure the I2C bus
i2c = I2C(0, I2C.MASTER, baudrate=100000)
i2c.scan() # returns list of slave addresses
i2c.writeto(0x42, 'hello') # send 5 bytes to slave with address 0x42
i2c.readfrom(0x42, 5) # receive 5 bytes from slave
i2c.readfrom_mem(0x42, 0x10, 2) # read 2 bytes from slave 0x42, slave memory 0x10
i2c.writeto_mem(0x42, 0x10, 'xy') # write 2 bytes to slave 0x42, slave memory 0x10
```

1.9 Watchdog timer (WDT)

See `machine.WDT`.

```
from machine import WDT

# enable the WDT with a timeout of 5s (1s is the minimum)
wdt = WDT(timeout=5000)
wdt.feed()
```

1.10 Real time clock (RTC)

See `machine.RTC`

```
import machine
from machine import RTC

rtc = machine.RTC() # init with default time and date
rtc = RTC(datetime=(2015, 8, 29, 9, 0, 0, 0, None)) # init with a specific time and date
print(rtc.now())

def alarm_handler (rtc_o):
    pass
    # do some non blocking operations
    # warning printing on an irq via telnet is not
    # possible, only via UART

# create a RTC alarm that expires after 5 seconds
rtc.alarm(time=5000, repeat=False)

# enable RTC interrupts
rtc_i = rtc.irq(trigger=RTC.ALARM0, handler=alarm_handler, wake=machine.SLEEP)

# go into suspended mode waiting for the RTC alarm to expire and wake us up
machine.sleep()
```

1.11 SD card

See `machine.SD`.

```
from machine import SD
import os

# clock pin, cmd pin, data0 pin
sd = SD(pins=('GP10', 'GP11', 'GP15'))
# or use default ones for the expansion board
sd = SD()
os.mount(sd, '/sd')
```

1.12 WLAN (WiFi)

See `network.WLAN` and `machine`.

```
import machine
from network import WLAN

# configure the WLAN subsystem in station mode (the default is AP)
wlan = WLAN(mode=WLAN.STA)
# go for fixed IP settings
wlan.ifconfig(config=('192.168.0.107', '255.255.255.0', '192.168.0.1', '8.8.8.8'))
wlan.scan() # scan for available networks
wlan.connect(ssid='mynetwork', auth=(WLAN.WPA2, 'mynetworkkey'))
while not wlan.isconnected():
    pass
print(wlan.ifconfig())
# enable wake on WLAN
wlan.irq(trigger=WLAN.ANY_EVENT, wake=machine.SLEEP)
# go to sleep
machine.sleep()
# now, connect to the FTP or the Telnet server and the WiPy will wake-up
```

1.13 Telnet and FTP server

See `network.Server`

```
from network import Server

# init with new user, password and seconds timeout
server = Server(login=('user', 'password'), timeout=60)
server.timeout(300) # change the timeout
server.timeout() # get the timeout
server.isrunning() # check wether the server is running or not
```

1.14 Heart beat LED

See `wipy`.


```
import wipy

wipy.heartbeat(False) # disable the heartbeat LED
wipy.heartbeat(True)  # enable the heartbeat LED
wipy.heartbeat()      # get the heartbeat state
```


GENERAL INFORMATION ABOUT THE WIPY

2.1 No floating point support

Due to space reasons, there's no floating point support, and no math module. This means that floating point numbers cannot be used anywhere in the code, and that all divisions must be performed using `//` instead of `/`. Example:

```
>>> r = 4 // 2 # this will work
>>> r = 4 / 2  # this WON'T
```

2.2 Before applying power

Warning: The GPIO pins of the WiPy are NOT 5V tolerant, connecting them to voltages higher than 3.6V will cause irreparable damage to the board. ADC pins, when configured in analog mode cannot withstand voltages above 1.8V. Keep these considerations in mind when wiring your electronics.

2.3 WLAN default behaviour

When the WiPy boots with the default factory configuration starts in Access Point mode with `ssid` that starts with: `wipy-wlan` and `key: www.wipy.io`. Connect to this network and the WiPy will be reachable at `192.168.1.1`. In order to gain access to the interactive prompt, open a telnet session to that IP address on the default port (23). You will be asked for credentials: `login: micro` and `password: python`

2.4 Telnet REPL

Linux stock telnet works like a charm (also on OSX), but other tools like putty work quite well too. The default credentials are: **user:** `micro`, **password:** `python`. See [network.server](#) for info on how to change the defaults. For instance, on a linux shell (when connected to the WiPy in AP mode):

```
$ telnet 192.168.1.1
```

2.5 Local file system and FTP access

There is a small internal file system (a drive) on the WiPy, called `/flash`, which is stored within the external serial flash memory. If a micro SD card is hooked-up and mounted, it will be available as well.

When the WiPy starts up, it always boots from the `boot.py` located in the `/flash` file system.

The file system is accessible via the native FTP server running in the WiPy. Open your FTP client of choice and connect to:

url: `ftp://192.168.1.1`, **user:** `micro`, **password:** `python`

See [network.server](#) for info on how to change the defaults. The recommended clients are: Linux stock FTP (also in OSX), Filezilla and FireFTP. For example, on a linux shell:

```
$ ftp 192.168.1.1
```

The FTP server on the WiPy doesn't support active mode, only passive, therefore, if using the native unix ftp client, just after logging in do:

```
ftp> passive
```

Besides that, the FTP server only supports one data connection at a time. Check out the Filezilla settings section below for more info.

2.6 FileZilla settings

Do not use the quick connect button, instead, open the site manager and create a new configuration. In the `General` tab make sure that encryption is set to: `Only use plain FTP (insecure)`. In the `Transfer Settings` tab limit the max number of connections to one, otherwise FileZilla will try to open a second command connection when retrieving and saving files, and for simplicity and to reduce code size, only one command and one data connections are possible. Other FTP clients might behave in a similar way.

2.7 Upgrading the firmware Over The Air

OTA software updates can be performed through the FTP server. Upload the `mcuimg.bin` file to: `/flash/sys/mcuimg.bin` it will take around 6s. You won't see the file being stored inside `/flash/sys/` because it's actually saved bypassing the user file system, so it ends up inside the internal **hidden** file system, but rest assured that it was successfully transferred, and it has been signed with a MD5 checksum to verify its integrity. Now, reset the WiPy by pressing the switch on the board, or by typing:

```
>>> import machine
>>> machine.reset()
```

Software updates can be found in: <https://github.com/wipy/wipy/releases> (**Binaries.zip**). It's always recommended to update to the latest software, but make sure to read the **release notes** before.

Note: The `bootloader.bin` found inside `Binaries.zip` is there only for reference, it's not needed for the Over The Air update.

In order to check your software version, do:

```
>>> import os
>>> os.uname().release
```

If the version number is lower than the latest release found in [the releases](#), go ahead and update your WiPy!

2.8 Boot modes and safe boot

If you power up normally, or press the reset button, the WiPy will boot into standard mode; the `boot.py` file will be executed first, then `main.py` will run.

You can override this boot sequence by pulling GP28 **up** (connect it to the 3v3 output pin) during reset. This procedure also allows going back in time to old firmware versions. The WiPy can hold up to 3 different firmware versions, which are: the factory firmware plus 2 user updates.

After reset, if GP28 is held high, the heartbeat LED will start flashing slowly, if after 3 seconds the pin is still being held high, the LED will start blinking a bit faster and the WiPy will select the previous user update to boot. If the previous user update is the desired firmware image, GP28 must be released before 3 more seconds elapse. If 3 seconds later the pin is still high, the factory firmware will be selected, the LED will flash quickly for 1.5 seconds and the WiPy will proceed to boot. The firmware selection mechanism is as follows:

Safe Boot Pin GP28 released during:

1st 3 secs window	2nd 3 secs window	Final 1.5 secs window
Safe boot, <i>latest</i> firmware is selected	Safe boot, <i>previous</i> user update selected	Safe boot, the <i>factory</i> firmware is selected

On all of the above 3 scenarios, safe boot mode is entered, meaning that the execution of both `boot.py` and `main.py` is skipped. This is useful to recover from crash situations caused by the user scripts. The selection made during safe boot is not persistent, therefore after the next normal reset the latest firmware will run again.

2.9 The heartbeat LED

By default the heartbeat LED flashes once every 4s to signal that the system is alive. This can be overridden through the `wipy` module:

```
>>> import wipy
>>> wipy.heartbeat(False)
```

There are currently 2 kinds of errors that you might see:

1. If the heartbeat LED flashes quickly, then a Python script (eg `main.py`) has an error. Use the REPL to debug it.
2. If the heartbeat LED stays on, then there was a hard fault, you cannot recover from this, the only way out is to press the reset switch.

2.10 Details on sleep modes

- `machine.idle()`: Power consumption: ~12mA (in WLAN STA mode). Wake sources: any hardware interrupt (including systick with period of 1ms), no special configuration required.
- `machine.sleep()`: 950uA (in WLAN STA mode). Wake sources are `Pin`, `RTC` and `WLAN`
- `machine.deepsleep()`: ~5uA. Wake sources are `Pin` and `RTC`.

WIPY TUTORIALS AND EXAMPLES

Before starting, make sure that you are running the latest firmware, for instructions see *OTA How-To*.

3.1 Introduction to the WiPy

To get the most out of your WiPy, there are a few basic things to understand about how it works.

3.1.1 Caring for your WiPy and expansion board

Because the WiPy/expansion board does not have a housing it needs a bit of care:

- Be gentle when plugging/unplugging the USB cable. Whilst the USB connector is well soldered and is relatively strong, if it breaks off it can be very difficult to fix.
- Static electricity can shock the components on the WiPy and destroy them. If you experience a lot of static electricity in your area (eg dry and cold climates), take extra care not to shock the WiPy. If your WiPy came in a ESD bag, then this bag is the best way to store and carry the WiPy as it will protect it against static discharges.

As long as you take care of the hardware, you should be okay. It's almost impossible to break the software on the WiPy, so feel free to play around with writing code as much as you like. If the filesystem gets corrupt, see below on how to reset it. In the worst case you might need to do a safe boot, which is explained in detail [here](#).

3.1.2 Plugging into the expansion board and powering on

The expansion board can power the WiPy via USB. The WiPy comes with a sticker on top of the RF shield that labels all pins, and this should match the label numbers on the expansion board headers. When plugging it in, the WiPy antenna will end up on top of the SD card connector of the expansion board. A video showing how to do this can be found [here](#).

3.1.3 Expansion board hardware guide

The document explaining the hardware details of the expansion board can be found [here](#).

3.1.4 Powering by an external power source

The WiPy can be powered by a battery or other external power source.

Be sure to connect the positive lead of the power supply to VIN, and ground to GND. There is no polarity protection on the WiPy so you must be careful when connecting anything to VIN.

- When powering via VIN:

The input voltage must be between 3.6V and 5.5V.

- When powering via 3V3:

The input voltage must be exactly 3V3, ripple free and from a supply capable of sourcing at least 300mA of current

3.1.5 Performing firmware upgrades

For detailed instructions see *OTA How-To*.

3.2 Getting a MicroPython REPL prompt

REPL stands for Read Evaluate Print Loop, and is the name given to the interactive MicroPython prompt that you can access on the WiPy. Using the REPL is by far the easiest way to test out your code and run commands. You can use the REPL in addition to writing scripts in `main.py`. To use the REPL, you must connect to the WiPy either via *telnet*, or with a USB to serial converter wired to one of the two UARTs on the WiPy. To enable REPL duplication on UART0 (the one accessible via the expansion board) do:

```
>>> from machine import UART
>>> import os
>>> uart = UART(0, 115200)
>>> os.dupterm(uart)
```

Place this piece of code inside your *boot.py* so that it's done automatically after reset.

3.2.1 Windows

First you need to install the FTDI drivers for the expansion board's USB to serial converter. Then you need a terminal software. The best option is to download the free program PuTTY: [putty.exe](#).

In order to get to the telnet REPL:

Using putty, select *Telnet* as connection type, leave the default port (23) and enter the IP address of your WiPy (192.168.1.1 when in *WLAN.AP* mode), then click open.

In order to get to the REPL UART:

Using your serial program you must connect to the COM port that you found in the previous step. With PuTTY, click on "Session" in the left-hand panel, then click the "Serial" radio button on the right, then enter you COM port (eg COM4) in the "Serial Line" box. Finally, click the "Open" button.

3.2.2 Mac OS X

Open a terminal and run:

```
$ telnet 192.168.1.1
```

or:

```
$ screen /dev/tty.usbmodem* 115200
```


When you are finished and want to exit `screen`, type CTRL-A CTRL-\. If your keyboard does not have a \-key (i.e. you need an obscure combination for \ like ALT-SHIFT-7) you can remap the `quit` command:

- create `~/.screenrc`
- add `bind q quit`

This will allow you to quit `screen` by hitting CTRL-A Q.

3.2.3 Linux

Open a terminal and run:

```
$ telnet 192.168.1.1
```

or:

```
$ screen /dev/ttyUSB0 115200
```

You can also try `picocom` or `minicom` instead of `screen`. You may have to use `/dev/ttyUSB01` or a higher number for `ttyUSB`. And, you may need to give yourself the correct permissions to access this devices (eg group `uucp` or `dialout`, or use `sudo`).

3.2.4 Using the REPL prompt

Now let's try running some MicroPython code directly on the WiPy.

With your serial program open (PuTTY, `screen`, `picocom`, etc) you may see a blank screen with a flashing cursor. Press Enter and you should be presented with a MicroPython prompt, i.e. `>>>`. Let's make sure it is working with the obligatory test:

```
>>> print("hello WiPy!")
hello WiPy!
```

In the above, you should not type in the `>>>` characters. They are there to indicate that you should type the text after it at the prompt. In the end, once you have entered the text `print("hello WiPy!")` and pressed Enter, the output on your screen should look like it does above.

If you already know some Python you can now try some basic commands here.

If any of this is not working you can try either a hard reset or a soft reset; see below.

Go ahead and try typing in some other commands. For example:

```
>>> from machine import Pin
>>> import wipy
>>> wipy.heartbeat(False) # disable the heartbeat
>>> led = Pin('GP25', mode=Pin.OUT)
>>> led(1)
>>> led(0)
>>> led.toggle()
>>> 1 + 2
3
>>> 4 // 2
2
>>> 20 * 'py'
'pypypypypypypypypypypypypypypypypypypypypypypypypypy'
```

3.2.5 Resetting the board

If something goes wrong, you can reset the board in two ways. The first is to press CTRL-D at the MicroPython prompt, which performs a soft reset. You will see a message something like:

```
>>>
PYB: soft reboot
MicroPython v1.4.6-146-g1d8b5e5 on 2015-10-21; WiPy with CC3200
Type "help()" for more information.
>>>
```

If that isn't working you can perform a hard reset (turn-it-off-and-on-again) by pressing the RST switch (the small black button next to the heartbeat LED). During telnet, this will end your session, disconnecting whatever program that you used to connect to the WiPy.

3.3 Getting started with Blynk and the WiPy

Blynk is a platform with iOS and Android apps to control Arduino, Raspberry Pi and the likes over the Internet. You can easily build graphic interfaces for all your projects by simply dragging and dropping widgets.

There are several examples available that work out-of-the-box with the WiPy. Before anything else, make sure that your WiPy is running the latest software, check *OTA How-To* for instructions.

1. Get the [Blynk library](#) and put it in `/flash/lib/` via FTP.
2. Get the [Blynk examples](#), edit the network settings, and afterwards upload them to `/flash/lib/` via FTP as well.
3. Follow the instructions on each example to setup the Blynk dashboard on your smartphone or tablet.
4. Give it a try, for instance:

```
>>> execfile('01_simple.py')
```

3.4 WLAN step by step

The WLAN is a system feature of the WiPy, therefore it is always enabled (even while in `machine.SLEEP`), except when deepsleep mode is entered.

In order to retrieve the current WLAN instance, do:

```
>>> from network import WLAN
>>> wlan = WLAN() # we call the constructor without params
```

You can check the current mode (which is always `WLAN.AP` after power up):

```
>>> wlan.mode()
```

Warning: When you change the WLAN mode following the instructions below, your WLAN connection to the WiPy will be broken. This means you will not be able to run these commands interactively over the WLAN.

There are two ways around this::

1. put this setup code into your *boot.py* file so that it gets executed automatically after reset.
2. *duplicate the REPL on UART*, so that you can run commands via USB.

3.4.1 Connecting to your home router

The WLAN network card always boots in `WLAN.AP` mode, so we must first configure it as a station:

```
from network import WLAN
wlan = WLAN(mode=WLAN.STA)
```

Now you can proceed to scan for networks:

```
nets = wlan.scan()
for net in nets:
    if net.ssid == 'mywifi':
        print('Network found!')
        wlan.connect(net.ssid, auth=(net.sec, 'mywifkey'), timeout=5000)
        while not wlan.isconnected():
            machine.idle() # save power while waiting
        print('WLAN connection succeeded!')
        break
```

3.4.2 Assigning a static IP address when booting

If you want your WiPy to connect to your home router after boot-up, and with a fixed IP address so that you can access it via telnet or FTP, use the following script as `/flash/boot.py`:

```
import machine
from network import WLAN
wlan = WLAN() # get current object, without changing the mode

if machine.reset_cause() != machine.SOFT_RESET:
    wlan.init(WLAN.STA)
    # configuration below MUST match your home router settings!!
    wlan.ifconfig(config=('192.168.178.107', '255.255.255.0', '192.168.178.1', '8.8.8.8'))

if not wlan.isconnected():
    # change the line below to match your network ssid, security and password
    wlan.connect('mywifi', auth=(WLAN.WPA2, 'mywifkey'), timeout=5000)
    while not wlan.isconnected():
        machine.idle() # save power while waiting
```

Note: Notice how we check for the reset cause and the connection status, this is crucial in order to be able to soft reset the WiPy during a telnet session without breaking the connection.

3.5 Reset and boot modes

There are soft resets and hard resets.

- A soft reset simply clears the state of the MicroPython virtual machine, but leaves hardware peripherals unaffected. To do a soft reset, simply press **Ctrl+D** on the REPL, or within a script do:

```
import sys
sys.exit()
```

- A hard reset is the same as performing a power cycle to the board. In order to hard reset the WiPy, press the switch on the board or:

```
import machine
machine.reset()
```

3.5.1 Safe boot

If something goes wrong with your WiPy, don't panic! It is almost impossible for you to break the WiPy by programming the wrong thing.

The first thing to try is to boot in safe mode: this temporarily skips execution of `boot.py` and `main.py` and gives default WLAN settings.

If you have problems with the filesystem you can *format the internal flash drive*.

To boot in safe mode, follow the detailed instructions described *here*.

In safe mode, the `boot.py` and `main.py` files are not executed, and so the WiPy boots up with default settings. This means you now have access to the filesystem, and you can edit `boot.py` and `main.py` to fix any problems.

Entering safe mode is temporary, and does not make any changes to the files on the WiPy.

3.5.2 Factory reset the filesystem

If you WiPy's filesystem gets corrupted (very unlikely, but possible), you can format it very easily by doing:

```
>>> import os
>>> os.mkfs('/flash')
```

Resetting the filesystem deletes all files on the internal WiPy storage (not the SD card), and restores the files `boot.py` and `main.py` back to their original state after the next reset.

MICROPYTHON LIBRARIES

This chapter describes modules (function and class libraries) which are built into MicroPython. There are a few categories of modules:

- Modules which implement a subset of standard Python functionality and are not intended to be extended by the user.
- Modules which implement a subset of Python functionality, with a provision for extension by the user (via Python code).
- Modules which implement MicroPython extensions to the Python standard libraries.
- Modules specific to a particular port and thus not portable.

Note about the availability of modules and their contents: This documentation in general aspires to describe all modules and functions/classes which are implemented in MicroPython. However, MicroPython is highly configurable, and each port to a particular board/embedded system makes available only a subset of MicroPython libraries. For officially supported ports, there is an effort to either filter out non-applicable items, or mark individual descriptions with “Availability:” clauses describing which ports provide a given feature. With that in mind, please still be warned that some functions/classes in a module (or even the entire module) described in this documentation may be unavailable in a particular build of MicroPython on a particular board. The best place to find general information of the availability/non-availability of a particular feature is the “General Information” section which contains information pertaining to a specific port.

Beyond the built-in libraries described in this documentation, many more modules from the Python standard library, as well as further MicroPython extensions to it, can be found in the [micropython-lib repository](#).

4.1 Python standard libraries and micro-libraries

The following standard Python libraries have been “micro-ified” to fit in with the philosophy of MicroPython. They provide the core functionality of that module and are intended to be a drop-in replacement for the standard Python library.

The modules are available by their u-name, and also by their non-u-name. The non-u-name can be overridden by a file of that name in your package path. For example, `import json` will first search for a file `json.py` or directory `json` and load that package if it is found. If nothing is found, it will fallback to loading the built-in `ujson` module.

4.1.1 Builtin Functions

All builtin functions are described here. They are also available via `builtins` module.

abs ()

all ()

`any()`
`bin()`
`class bool`
`class bytearray`
`class bytes`
`callable()`
`chr()`
`classmethod()`
`compile()`
`class complex`
`class dict`
`dir()`
`divmod()`
`enumerate()`
`eval()`
`exec()`
`filter()`
`class float`
`class frozenset`
`getattr()`
`globals()`
`hasattr()`
`hash()`
`hex()`
`id()`
`input()`
`class int`
`isinstance()`
`issubclass()`
`iter()`
`len()`
`class list`
`locals()`
`map()`
`max()`
`class memoryview`

`min()`
`next()`
`class object`
`oct()`
`open()`
`ord()`
`pow()`
`print()`
`property()`
`range()`
`repr()`
`reversed()`
`round()`
`class set`
`setattr()`
`sorted()`
`staticmethod()`
`class str`
`sum()`
`super()`
`class tuple`
`type()`
`zip()`

4.1.2 gc – control the garbage collector

Functions

`gc.enable()`

Enable automatic garbage collection.

`gc.disable()`

Disable automatic garbage collection. Heap memory can still be allocated, and garbage collection can still be initiated manually using `gc.collect()`.

`gc.collect()`

Run a garbage collection.

`gc.mem_alloc()`

Return the number of bytes of heap RAM that are allocated.

`gc.mem_free()`

Return the number of bytes of available heap RAM.

4.1.3 `select` – wait for events on a set of streams

This module provides functions to wait for events on streams (select streams which are ready for operations).

Pyboard specifics

Polling is an efficient way of waiting for read/write activity on multiple objects. Current objects that support polling are: `pyb.UART`, `pyb.USB_VCP`.

Functions

`select.poll()`

Create an instance of the `Poll` class.

`select.select(rlist, wlist, xlist[, timeout])`

Wait for activity on a set of objects.

This function is provided for compatibility and is not efficient. Usage of `Poll` is recommended instead.

class `Poll`

Methods

`poll.register(obj[, eventmask])`

Register `obj` for polling. `eventmask` is logical OR of:

- `select.POLLIN` - data available for reading
- `select.POLLOUT` - more data can be written
- `select.POLLERR` - error occurred
- `select.POLLHUP` - end of stream/connection termination detected

`eventmask` defaults to `select.POLLIN | select.POLLOUT`.

`poll.unregister(obj)`

Unregister `obj` from polling.

`poll.modify(obj, eventmask)`

Modify the `eventmask` for `obj`.

`poll.poll([timeout])`

Wait for at least one of the registered objects to become ready. Returns list of `(obj, event, ...)` tuples, `event` element specifies which events happened with a stream and is a combination of `select.POLL*` constants described above. There may be other elements in tuple, depending on a platform and version, so don't assume that its size is 2. In case of timeout, an empty list is returned.

Timeout is in milliseconds.

4.1.4 `sys` – system specific functions

Functions

`sys.exit(retval=0)`

Terminate current program with a given exit code. Underlyingly, this function raise as `SystemExit` exception.

If an argument is given, its value given as an argument to `SystemExit`.

`sys.print_exception(exc, file=sys.stdout)`

Print exception with a traceback to a file-like object *file* (or `sys.stdout` by default).

Difference to CPython

This is simplified version of a function which appears in the `traceback` module in CPython. Unlike `traceback.print_exception()`, this function takes just exception value instead of exception type, exception value, and traceback object; *file* argument should be positional; further arguments are not supported. CPython-compatible `traceback` module can be found in `micropython-lib`.

Constants

`sys.argv`

A mutable list of arguments the current program was started with.

`sys.byteorder`

The byte order of the system (“little” or “big”).

`sys.implementation`

Object with information about the current Python implementation. For MicroPython, it has following attributes:

- *name* - string “micropython”
- *version* - tuple (major, minor, micro), e.g. (1, 7, 0)

This object is the recommended way to distinguish MicroPython from other Python implementations (note that it still may not exist in the very minimal ports).

Difference to CPython

CPython mandates more attributes for this object, but the actual useful bare minimum is implemented in MicroPython.

`sys.maxsize`

Maximum value which a native integer type can hold on the current platform, or maximum value representable by MicroPython integer type, if it’s smaller than platform max value (that is the case for MicroPython ports without long int support).

This attribute is useful for detecting “bitness” of a platform (32-bit vs 64-bit, etc.). It’s recommended to not compare this attribute to some value directly, but instead count number of bits in it:

```
bits = 0
v = sys.maxsize
while v:
    bits += 1
    v >>= 1
if bits > 32:
    # 64-bit (or more) platform
    ...
else:
    # 32-bit (or less) platform
    # Note that on 32-bit platform, value of bits may be less than 32
    # (e.g. 31) due to peculiarities described above, so use "> 16",
    # "> 32", "> 64" style of comparisons.
```

sys.modules

Dictionary of loaded modules. On some ports, it may not include builtin modules.

sys.path

A mutable list of directories to search for imported modules.

sys.platform

The platform that MicroPython is running on. For OS/RTOS ports, this is usually an identifier of the OS, e.g. "linux". For baremetal ports it is an identifier of a board, e.g. "pyboard" for the original MicroPython reference board. It thus can be used to distinguish one board from another. If you need to check whether your program runs on MicroPython (vs other Python implementation), use `sys.implementation` instead.

sys.stderr

Standard error stream.

sys.stdin

Standard input stream.

sys.stdout

Standard output stream.

sys.version

Python language version that this implementation conforms to, as a string.

sys.version_info

Python language version that this implementation conforms to, as a tuple of ints.

4.1.5 ubinascii – binary/ASCII conversions

This module implements conversions between binary data and various encodings of it in ASCII form (in both directions).

Functions

`ubinascii.hexlify(data[, sep])`

Convert binary data to hexadecimal representation. Returns bytes string.

Difference to CPython

If additional argument, `sep` is supplied, it is used as a separator between hexadecimal values.

`ubinascii.unhexlify(data)`

Convert hexadecimal data to binary representation. Returns bytes string. (i.e. inverse of `hexlify`)

`ubinascii.a2b_base64(data)`

Convert Base64-encoded data to binary representation. Returns bytes string.

`ubinascii.b2a_base64(data)`

Encode binary data in Base64 format. Returns string.

4.1.6 ujson – JSON encoding and decoding

This modules allows to convert between Python objects and the JSON data format.

Functions

`ujson.dumps(obj)`

Return `obj` represented as a JSON string.

`ujson.loads(str)`

Parse the JSON `str` and return an object. Raises `ValueError` if the string is not correctly formed.

4.1.7 uos – basic “operating system” services

The `os` module contains functions for filesystem access and `urandom` function.

Port specifics

The filesystem has `/` as the root directory and the available physical drives are accessible from here. They are currently:

`/flash` – the internal flash filesystem

`/sd` – the SD card (if it exists)

On boot up, the current directory is `/flash`.

Functions

`uos.chdir(path)`

Change current directory.

`uos.getcwd()`

Get the current directory.

`uos.listdir([dir])`

With no argument, list the current directory. Otherwise list the given directory.

`uos.mkdir(path)`

Create a new directory.

`uos.remove(path)`

Remove a file.

`uos.rmdir(path)`

Remove a directory.

`uos.rename(old_path, new_path)`

Rename a file.

`uos.stat(path)`

Get the status of a file or directory.

`uos.sync()`

Sync all filesystems.

`uos.urandom(n)`

Return a bytes object with `n` random bytes, generated by the hardware random number generator.

`uos.mount(block_device, mount_point, *, readonly=False)`

Mounts a block device (like an SD object) in the specified mount point. Example:

```
os.mount(sd, '/sd')
```

`uos.unmount` (*path*)

Unmounts a previously mounted block device from the given path.

`uos.mkfs` (*block_device or path*)

Formats the specified path, must be either `/flash` or `/sd`. A block device can also be passed like an SD object before being mounted.

`uos.dupterm` (*stream_object*)

Duplicate the terminal (the REPL) on the passed stream-like object. The given object must at least implement the `.read()` and `.write()` methods.

Constants

`uos.sep`

separation character used in paths

4.1.8 ure – regular expressions

This module implements regular expression operations. Regular expression syntax supported is a subset of CPython `re` module (and actually is a subset of POSIX extended regular expressions).

Supported operators are:

'.' Match any character.

'[]' Match set of characters. Individual characters and ranges are supported.

'^'

'\$'

'?'

'*'

'+'

'??'

'*?'

'+?'

Counted repetitions (`{m, n}`), more advanced assertions, named groups, etc. are not supported.

Functions

`ure.compile` (*regex*)

Compile regular expression, return `regex` object.

`ure.match` (*regex, string*)

Match `regex` against `string`. Match always happens from starting position in a string.

`ure.search` (*regex, string*)

Search `regex` in a `string`. Unlike `match`, this will search `string` for first position which matches `regex` (which still may be 0 if `regex` is anchored).

`ure.DEBUG`

Flag value, display debug information about compiled expression.

Regex objects

Compiled regular expression. Instances of this class are created using `ure.compile()`.

`regex.match(string)`

`regex.search(string)`

`regex.split(string, max_split=-1)`

Match objects

Match objects as returned by `match()` and `search()` methods.

`match.group([index])`

Only numeric groups are supported.

4.1.9 usocket – socket module

This module provides access to the BSD socket interface.

See corresponding [CPython module](#) for comparison.

Socket address format(s)

Functions below which expect a network address, accept it in the format of `(ipv4_address, port)`, where `ipv4_address` is a string with dot-notation numeric IPv4 address, e.g. "8.8.8.8", and port is integer port number in the range 1-65535. Note the domain names are not accepted as `ipv4_address`, they should be resolved first using `socket.getaddrinfo()`.

Functions

`socket.socket(socket.AF_INET, socket.SOCK_STREAM, socket.IPPROTO_TCP)`

Create a new socket using the given address family, socket type and protocol number.

Note: SSL sockets need to be created the following way before wrapping them with `ssl.wrap_socket`:

```
import socket
import ssl
s = socket.socket(socket.AF_INET, socket.SOCK_STREAM, socket.IPPROTO_SEC)
ss = ssl.wrap_socket(s)
```

`socket.getaddrinfo(host, port)`

Translate the host/port argument into a sequence of 5-tuples that contain all the necessary arguments for creating a socket connected to that service. The list of 5-tuples has following structure:

```
(family, type, proto, canonname, sockaddr)
```

The following example shows how to connect to a given url:

```
s = socket.socket()
s.connect(socket.getaddrinfo('www.micropython.org', 80)[0][-1])
```

Exceptions

`socket.error`

`socket.timeout`

Constants

`socket.AF_INET`
family types

`socket.SOCK_STREAM`

`socket.SOCK_DGRAM`
socket types

`socket.IPPROTO_UDP`

`socket.IPPROTO_TCP`

`socket.IPPROTO_SEC`
protocol numbers

class `socket`

Methods

`socket.close()`

Mark the socket closed. Once that happens, all future operations on the socket object will fail. The remote end will receive no more data (after queued data is flushed).

Sockets are automatically closed when they are garbage-collected, but it is recommended to close() them explicitly, or to use a with statement around them.

`socket.bind(address)`

Bind the socket to address. The socket must not already be bound.

`socket.listen([backlog])`

Enable a server to accept connections. If backlog is specified, it must be at least 0 (if it's lower, it will be set to 0); and specifies the number of unaccepted connections that the system will allow before refusing new connections. If not specified, a default reasonable value is chosen.

`socket.accept()`

Accept a connection. The socket must be bound to an address and listening for connections. The return value is a pair (conn, address) where conn is a new socket object usable to send and receive data on the connection, and address is the address bound to the socket on the other end of the connection.

`socket.connect(address)`

Connect to a remote socket at address.

`socket.send(bytes)`

Send data to the socket. The socket must be connected to a remote socket.

`socket.sendall(bytes)`

Send data to the socket. The socket must be connected to a remote socket.

`socket.recv(bufsize)`

Receive data from the socket. The return value is a bytes object representing the data received. The maximum amount of data to be received at once is specified by `bufsize`.

`socket.sendto(bytes, address)`

Send data to the socket. The socket should not be connected to a remote socket, since the destination socket is specified by `address`.

`socket.recvfrom(bufsize)`

Receive data from the socket. The return value is a pair (bytes, address) where bytes is a bytes object representing the data received and address is the address of the socket sending the data.

`socket.setsockopt(level, optname, value)`

Set the value of the given socket option. The needed symbolic constants are defined in the socket module (`SO_*` etc.). The value can be an integer or a bytes-like object representing a buffer.

`socket.settimeout(value)`

Set a timeout on blocking socket operations. The value argument can be a nonnegative floating point number expressing seconds, or `None`. If a non-zero value is given, subsequent socket operations will raise a timeout exception if the timeout period value has elapsed before the operation has completed. If zero is given, the socket is put in non-blocking mode. If `None` is given, the socket is put in blocking mode.

`socket.setblocking(flag)`

Set blocking or non-blocking mode of the socket: if `flag` is false, the socket is set to non-blocking, else to blocking mode.

This method is a shorthand for certain `settimeout()` calls:

```
sock.setblocking(True) is equivalent to sock.settimeout(None)
sock.setblocking(False) is equivalent to sock.settimeout(0.0)
```

`socket.makefile(mode='rb')`

Return a file object associated with the socket. The exact returned type depends on the arguments given to `makefile()`. The support is limited to binary modes only ('rb' and 'wb'). CPython's arguments: `encoding`, `errors` and `newline` are not supported.

The socket must be in blocking mode; it can have a timeout, but the file object's internal buffer may end up in a inconsistent state if a timeout occurs.

Difference to CPython

Closing the file object returned by `makefile()` WILL close the original socket as well.

`socket.read(size)`

Read up to `size` bytes from the socket. Return a bytes object. If `size` is not given, it behaves just like `socket.readall()`, see below.

`socket.readall()`

Read all data available from the socket until EOF. This function will not return until the socket is closed.

`socket.readinto(buf[, nbytes])`

Read bytes into the `buf`. If `nbytes` is specified then read at most that many bytes. Otherwise, read at most `len(buf)` bytes.

Return value: number of bytes read and stored into `buf`.

`socket.readline()`

Read a line, ending in a newline character.

Return value: the line read.

`socket.write(buf)`

Write the buffer of bytes to the socket.

Return value: number of bytes written.

4.1.10 `ussl` – `ssl` module

This module provides access to Transport Layer Security (often known as “Secure Sockets Layer”) encryption and peer authentication facilities for network sockets, both client-side and server-side.

Functions

`ssl.wrap_socket(sock, keyfile=None, certfile=None, server_side=False, cert_reqs=CERT_NONE, ca_certs=None)`

Takes an instance `sock` of `socket.socket`, and returns an instance of `ssl.SSLSocket`, a subtype of `socket.socket`, which wraps the underlying socket in an SSL context. `sock` must be a `SOCK_STREAM` socket and protocol number `socket.IPPROTO_SEC`; other socket types are unsupported. Example:

```
import socket
import ssl
s = socket(socket.AF_INET, socket.SOCK_STREAM, socket.IPPROTO_SEC)
ss = ssl.wrap_socket(s)
ss.connect(socket.getaddrinfo('www.google.com', 443)[0][-1])
```

Certificates must be used in order to validate the other side of the connection, and also to authenticate ourselves with the other end. Such certificates must be stored as files using the `FTP` server, and they must be placed in specific paths with specific names.

- The certificate to validate the other side goes in: `‘/flash/cert/ca.pem’`
- The certificate to authenticate ourselves goes in: `‘/flash/cert/cert.pem’`
- The key for our own certificate goes in: `‘/flash/cert/private.key’`

Note: When these files are stored, they are placed inside the internal `hidden` file system (just like firmware updates), and therefore they are never visible.

For instance to connect to the Blynk servers using certificates, take the file `ca.pem` located in the `blynk examples` folder and put it in `‘/flash/cert/’`. Then do:

```
import socket
import ssl
s = socket.socket(socket.AF_INET, socket.SOCK_STREAM, socket.IPPROTO_SEC)
ss = ssl.wrap_socket(s, cert_reqs=ssl.CERT_REQUIRED, ca_certs='/flash/cert/ca.pem')
ss.connect(socket.getaddrinfo('cloud.blynk.cc', 8441)[0][-1])
```

SSL sockets inherit all methods and from the standard sockets, see the `usocket` module.

Exceptions

`ssl.SSLError`

Constants

`ssl.CERT_NONE`

`ssl.CERT_OPTIONAL`

`ssl.CERT_REQUIRED`

supported values in `cert_reqs`

4.1.11 `utime` – time related functions

The `utime` module provides functions for getting the current time and date, measuring time intervals, and for delays.

Time Epoch: Unix port uses standard for POSIX systems epoch of 1970-01-01 00:00:00 UTC. However, embedded ports use epoch of 2000-01-01 00:00:00 UTC.

Maintaining actual calendar date/time: This requires a Real Time Clock (RTC). On systems with underlying OS (including some RTOS), an RTC may be implicit. Setting and maintaining actual calendar time is responsibility of OS/RTOS and is done outside of MicroPython, it just uses OS API to query date/time. On baremetal ports however system time depends on `machine.RTC()` object. The current calendar time may be set using `machine.RTC().datetime(tuple)` function, and maintained by following means:

- By a backup battery (which may be an additional, optional component for a particular board).
- Using networked time protocol (requires setup by a port/user).
- Set manually by a user on each power-up (many boards then maintain RTC time across hard resets, though some may require setting it again in such case).

If actual calendar time is not maintained with a system/MicroPython RTC, functions below which require reference to current absolute time may behave not as expected.

Functions

`utime.localtime([secs])`

Convert a time expressed in seconds since the Epoch (see above) into an 8-tuple which contains: (year, month, mday, hour, minute, second, weekday, yearday) If `secs` is not provided or `None`, then the current time from the RTC is used.

- year includes the century (for example 2014).
- month is 1-12
- mday is 1-31
- hour is 0-23
- minute is 0-59
- second is 0-59
- weekday is 0-6 for Mon-Sun
- yearday is 1-366

`utime.mktime()`

This is inverse function of `localtime`. It's argument is a full 8-tuple which expresses a time as per `localtime`. It returns an integer which is the number of seconds since Jan 1, 2000.

`utime.sleep(seconds)`

Sleep for the given number of seconds.

`utime.sleep_ms(ms)`

Delay for given number of milliseconds, should be positive or 0.

`utime.sleep_us(us)`

Delay for given number of microseconds, should be positive or 0

`utime.ticks_ms()`

Returns an increasing millisecond counter with arbitrary reference point, that wraps after some (unspecified) value. The value should be treated as opaque, suitable for use only with `ticks_diff()`.

`utime.ticks_us()`

Just like `ticks_ms` above, but in microseconds.

`utime.ticks_cpu()`

Similar to `ticks_ms` and `ticks_us`, but with higher resolution (usually CPU clocks).

`utime.ticks_diff(old, new)`

Measure period between consecutive calls to `ticks_ms()`, `ticks_us()`, or `ticks_cpu()`. The value returned by these functions may wrap around at any time, so directly subtracting them is not supported. `ticks_diff()` should be used instead. “old” value should actually precede “new” value in time, or result is undefined. This function should not be used to measure arbitrarily long periods of time (because `ticks_*` functions wrap around and usually would have short period). The expected usage pattern is implementing event polling with timeout:

```
# Wait for GPIO pin to be asserted, but at most 500us
start = time.ticks_us()
while pin.value() == 0:
    if time.ticks_diff(start, time.ticks_us()) > 500:
        raise TimeoutError
```

`utime.time()`

Returns the number of seconds, as an integer, since the Epoch, assuming that underlying RTC is set and maintained as described above. If an RTC is not set, this function returns number of seconds since a port-specific reference point in time (for embedded boards without a battery-backed RTC, usually since power up or reset). If you want to develop portable MicroPython application, you should not rely on this function to provide higher than second precision. If you need higher precision, use `ticks_ms()` and `ticks_us()` functions, if you need calendar time, `localtime()` without an argument is a better choice.

Difference to CPython

In CPython, this function returns number of seconds since Unix epoch, 1970-01-01 00:00 UTC, as a floating-point, usually having microsecond precision. With MicroPython, only Unix port uses the same Epoch, and if floating-point precision allows, returns sub-second precision. Embedded hardware usually doesn't have floating-point precision to represent both long time ranges and subsecond precision, so they use integer value with second precision. Some embedded hardware also lacks battery-powered RTC, so returns number of seconds since last power-up or from other relative, hardware-specific point (e.g. reset).

4.2 MicroPython-specific libraries

Functionality specific to the MicroPython implementation is available in the following libraries.

4.2.1 `machine` — functions related to the board

The `machine` module contains specific functions related to the board.

Reset related functions

`machine.reset()`

Resets the device in a manner similar to pushing the external RESET button.

`machine.reset_cause()`

Get the reset cause. See *constants* for the possible return values.

Interrupt related functions

`machine.disable_irq()`

Disable interrupt requests. Returns the previous IRQ state: `False/True` for disabled/enabled IRQs respectively. This return value can be passed to `enable_irq` to restore the IRQ to its original state.

`machine.enable_irq(state=True)`

Enable interrupt requests. If `state` is `True` (the default value) then IRQs are enabled. If `state` is `False` then IRQs are disabled. The most common use of this function is to pass it the value returned by `disable_irq` to exit a critical section.

Power related functions

`machine.freq()`

Returns a tuple of clock frequencies: `(sysclk,)` These correspond to:

- `sysclk`: frequency of the CPU

`machine.idle()`

Gates the clock to the CPU, useful to reduce power consumption at any time during short or long periods. Peripherals continue working and execution resumes as soon as any interrupt is triggered (on many ports this includes system timer interrupt occurring at regular intervals on the order of millisecond).

`machine.sleep()`

Stops the CPU and disables all peripherals except for WLAN. Execution is resumed from the point where the sleep was requested. For wake up to actually happen, wake sources should be configured first.

`machine.deepsleep()`

Stops the CPU and all peripherals (including networking interfaces, if any). Execution is resumed from the main script, just as with a reset. The reset cause can be checked to know that we are coming from `machine.DEEPSLEEP`. For wake up to actually happen, wake sources should be configured first, like `Pin` change or RTC timeout.

`machine.wake_reason()`

Get the wake reason. See *constants* for the possible return values.

Miscellaneous functions

`machine.main(filename)`

Set the filename of the main script to run after `boot.py` is finished. If this function is not called then the default file `main.py` will be executed.

It only makes sense to call this function from within `boot.py`.

`machine.rng()`

Return a 24-bit software generated random number.

`machine.unique_id()`

Returns a byte string with a unique identifier of a board/SoC. It will vary from a board/SoC instance to another, if underlying hardware allows. Length varies by hardware (so use substring of a full value if you expect a short ID). In some MicroPython ports, ID corresponds to the network MAC address.

`machine.time_pulse_us(pin, pulse_level, timeout_us=1000000)`

Time a pulse on the given *pin*, and return the duration of the pulse in microseconds. The *pulse_level* argument should be 0 to time a low pulse or 1 to time a high pulse.

The function first waits while the pin input is different to the *pulse_level* parameter, then times the duration that the pin is equal to *pulse_level*. If the pin is already equal to *pulse_level* then timing starts straight away.

The function will raise an `OSError` with `ETIMEDOUT` if either of the waits is longer than the given timeout value (which is in microseconds).

Constants

`machine.IDLE`

`machine.SLEEP`

`machine.DEEPSLEEP`

irq wake values

`machine.POWER_ON`

`machine.HARD_RESET`

`machine.WDT_RESET`

`machine.DEEPSLEEP_RESET`

`machine.SOFT_RESET`

reset causes

`machine.WLAN_WAKE`

`machine.PIN_WAKE`

`machine.RTC_WAKE`

wake reasons

Classes

class `ADC` – analog to digital conversion

Usage:

```
import machine

adc = machine.ADC()           # create an ADC object
apin = adc.channel(pin='GP3') # create an analog pin on GP3
val = apin()                 # read an analog value
```

Constructors

`class machine.ADC(id=0, *, bits=12)`

Create an ADC object associated with the given pin. This allows you to then read analog values on that pin. For more info check the [pinout and alternate functions table](#).

Warning: ADC pin input range is 0-1.4V (being 1.8V the absolute maximum that it can withstand). When GP2, GP3, GP4 or GP5 are remapped to the ADC block, 1.8 V is the maximum. If these pins are used in digital mode, then the maximum allowed input is 3.6V.

Methods

`ADC.channel(id, *, pin)`

Create an analog pin. If only channel ID is given, the correct pin will be selected. Alternatively, only the pin can be passed and the correct channel will be selected. Examples:

```
# all of these are equivalent and enable ADC channel 1 on GP3
apin = adc.channel(1)
apin = adc.channel(pin='GP3')
apin = adc.channel(id=1, pin='GP3')
```

`ADC.init()`

Enable the ADC block.

`ADC.deinit()`

Disable the ADC block.

class ADCChannel — read analog values from internal or external sources

ADC channels can be connected to internal points of the MCU or to GPIO pins. ADC channels are created using the `ADC.channel` method.

`machine.adcchannel()`

Fast method to read the channel value.

`adcchannel.value()`

Read the channel value.

`adcchannel.init()`

Re-init (and effectively enable) the ADC channel.

`adcchannel.deinit()`

Disable the ADC channel.

class I2C – a two-wire serial protocol

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

I2C objects are created attached to a specific bus. They can be initialised when created, or initialised later on.

Example:

```
from machine import I2C

i2c = I2C(0) # create on bus 0
i2c = I2C(0, I2C.MASTER) # create and init as a master
i2c.init(I2C.MASTER, baudrate=20000) # init as a master
i2c.deinit() # turn off the peripheral
```

Printing the `i2c` object gives you information about its configuration.

A master must specify the recipient's address:

```
i2c.init(I2C.MASTER)
i2c.writeto(0x42, '123')           # send 3 bytes to slave with address 0x42
i2c.writeto(addr=0x42, b'456')   # keyword for address
```

Master also has other methods:

```
i2c.scan()                        # scan for slaves on the bus, returning
                                # a list of valid addresses
i2c.readfrom_mem(0x42, 2, 3)     # read 3 bytes from memory of slave 0x42,
                                # starting at address 2 in the slave
i2c.writeto_mem(0x42, 2, 'abc')  # write 'abc' (3 bytes) to memory of slave 0x42
                                # starting at address 2 in the slave, timeout after 1 second
```

Constructors

class `machine.I2C` (*bus*, ...)

Construct an I2C object on the given bus. *bus* can only be 0. If the bus is not given, the default one will be selected (0).

General Methods

I2C.init (*mode*, *, *baudrate*=100000, *pins*=(*SDA*, *SCL*))

Initialise the I2C bus with the given parameters:

- *mode* must be `I2C.MASTER`
- *baudrate* is the SCL clock rate
- *pins* is an optional tuple with the pins to assign to the I2C bus.

I2C.deinit ()

Turn off the I2C bus.

Availability: WiPy.

I2C.scan ()

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

Note: on WiPy the I2C object must be in master mode for this method to be valid.

Primitive I2C operations The following methods implement the primitive I2C master bus operations and can be combined to make any I2C transaction. They are provided if you need more control over the bus, otherwise the standard methods (see below) can be used.

I2C.start ()

Send a start bit on the bus (SDA transitions to low while SCL is high).

Availability: ESP8266.

I2C.stop ()

Send a stop bit on the bus (SDA transitions to high while SCL is high).

Availability: ESP8266.

I2C.readinto (*buf*)

Reads bytes from the bus and stores them into *buf*. The number of bytes read is the length of *buf*. An ACK will be sent on the bus after receiving all but the last byte, and a NACK will be sent following the last byte.

Availability: ESP8266.

I2C.write (*buf*)

Write all the bytes from *buf* to the bus. Checks that an ACK is received after each byte and raises an `OSError` if not.

Availability: ESP8266.

Standard bus operations The following methods implement the standard I2C master read and write operations that target a given slave device.

I2C.readfrom (*addr, nbytes*)

Read *nbytes* from the slave specified by *addr*. Returns a *bytes* object with the data read.

I2C.readfrom_into (*addr, buf*)

Read into *buf* from the slave specified by *addr*. The number of bytes read will be the length of *buf*.

On WiPy the return value is the number of bytes read. Otherwise the return value is *None*.

I2C.writeto (*addr, buf, *, stop=True*)

Write the bytes from *buf* to the slave specified by *addr*.

The *stop* argument (only available on WiPy) tells if a stop bit should be sent at the end of the transfer. If *False* the transfer should be continued later on.

On WiPy the return value is the number of bytes written. Otherwise the return value is *None*.

Memory operations Some I2C devices act as a memory device (or set of registers) that can be read from and written to. In this case there are two addresses associated with an I2C transaction: the slave address and the memory address. The following methods are convenience functions to communicate with such devices.

I2C.readfrom_mem (*addr, memaddr, nbytes, *, addrsize=8*)

Read *nbytes* from the slave specified by *addr* starting from the memory address specified by *memaddr*. The argument *addrsize* specifies the address size in bits (on ESP8266 this argument is not recognised and the address size is always 8 bits). Returns a *bytes* object with the data read.

I2C.readfrom_mem_into (*addr, memaddr, buf, *, addrsize=8*)

Read into *buf* from the slave specified by *addr* starting from the memory address specified by *memaddr*. The number of bytes read is the length of *buf*. The argument *addrsize* specifies the address size in bits (on ESP8266 this argument is not recognised and the address size is always 8 bits).

On WiPy the return value is the number of bytes read. Otherwise the return value is *None*.

I2C.writeto_mem (*addr, memaddr, buf, *, addrsize=8*)

Write *buf* to the slave specified by *addr* starting from the memory address specified by *memaddr*. The argument *addrsize* specifies the address size in bits (on ESP8266 this argument is not recognised and the address size is always 8 bits).

On WiPy the return value is the number of bytes written. Otherwise the return value is *None*.

Constants**I2C.MASTER**

for initialising the bus to master mode

Availability: WiPy.

class Pin – control I/O pins

A pin is the basic object to control I/O pins (also known as GPIO - general-purpose input/output). It has methods to set the mode of the pin (input, output, etc) and methods to get and set the digital logic level. For analog control of a pin, see the ADC class.

Usage Model:

Board pins are identified by their string id:

```
from machine import Pin
g = machine.Pin('GP9', mode=Pin.OUT, pull=None, drive=Pin.MED_POWER, alt=-1)
```

You can also configure the Pin to generate interrupts. For instance:

```
from machine import Pin

def pincb(pin):
    print(pin.id())

pin_int = Pin('GP10', mode=Pin.IN, pull=Pin.PULL_DOWN)
pin_int.irq(trigger=Pin.IRQ_RISING, handler=pincb)
# the callback can be triggered manually
pin_int.irq()
# to disable the callback
pin_int.irq().disable()
```

Now every time a falling edge is seen on the gpio pin, the callback will be executed. Caution: mechanical push buttons have “bounce” and pushing or releasing a switch will often generate multiple edges. See: <http://www.eng.utah.edu/~cs5780/debouncing.pdf> for a detailed explanation, along with various techniques for debouncing.

All pin objects go through the pin mapper to come up with one of the gpio pins.

Constructors

class `machine.Pin` (*id*, ...)

Create a new Pin object associated with the id. If additional arguments are given, they are used to initialise the pin. See `Pin.init()`.

Methods

`Pin.init` (*mode*, *pull*, *, *drive*, *alt*)

Initialise the pin:

•mode can be one of:

- Pin.IN - input pin.
- Pin.OUT - output pin in push-pull mode.
- Pin.OPEN_DRAIN - output pin in open-drain mode.
- Pin.ALT - pin mapped to an alternate function.
- Pin.ALT_OPEN_DRAIN - pin mapped to an alternate function in open-drain mode.

•pull can be one of:

- None - no pull up or down resistor.
- Pin.PULL_UP - pull up resistor enabled.

-Pin.PULL_DOWN - pull down resistor enabled.

•drive can be one of:

-Pin.LOW_POWER - 2mA drive capability.

-Pin.MED_POWER - 4mA drive capability.

-Pin.HIGH_POWER - 6mA drive capability.

•alt is the number of the alternate function. Please refer to the [pinout and alternate functions table](#). for the specific alternate functions that each pin supports.

Returns: None.

Pin.**id**()

Get the pin id.

Pin.**value**([value])

Get or set the digital logic level of the pin:

•With no argument, return 0 or 1 depending on the logic level of the pin.

•With value given, set the logic level of the pin. value can be anything that converts to a boolean. If it converts to True, the pin is set high, otherwise it is set low.

Pin.**__call__**([value])

Pin objects are callable. The call method provides a (fast) shortcut to set and get the value of the pin. See [Pin.value\(\)](#) for more details.

Pin.**alt_list**()

Returns a list of the alternate functions supported by the pin. List items are a tuple of the form: ('ALT_FUN_NAME', ALT_FUN_INDEX)

Availability: WiPy.

Pin.**toggle**()

Toggle the value of the pin.

Pin.**mode**([mode])

Get or set the pin mode.

Pin.**pull**([pull])

Get or set the pin pull.

Pin.**drive**([drive])

Get or set the pin drive strength.

Pin.**irq**(* , trigger, priority=1, handler=None, wake=None)

Create a callback to be triggered when the input level at the pin changes.

•trigger configures the pin level which can generate an interrupt. Possible values are:

-Pin.IRQ_FALLING interrupt on falling edge.

-Pin.IRQ_RISING interrupt on rising edge.

-Pin.IRQ_LOW_LEVEL interrupt on low level.

-Pin.IRQ_HIGH_LEVEL interrupt on high level.

The values can be *ORed* together, for instance mode=Pin.IRQ_FALLING | Pin.IRQ_RISING

•priority level of the interrupt. Can take values in the range 1-7. Higher values represent higher priorities.

•handler is an optional function to be called when new characters arrive.

•wakes selects the power mode in which this interrupt can wake up the board. Please note:

-If `wake_from=machine.Sleep.ACTIVE` any pin can wake the board.

-If `wake_from=machine.Sleep.SUSPENDED` pins GP2, GP4, GP10, GP11, GP17⁴ or GP24 can wake the board. Note that only 1 of this pins can be enabled as a wake source at the same time, so, only the last enabled pin as a `machine.Sleep.SUSPENDED` wake source will have effect.

-If `wake_from=machine.Sleep.SUSPENDED` pins GP2, GP4, GP10, GP11, GP17 and GP24 can wake the board. In this case all of the 6 pins can be enabled as a `machine.Sleep.HIBERNATE` wake source at the same time.

-Values can be ORed to make a pin generate interrupts in more than one power mode.

Returns a callback object.

Attributes

class `Pin.board`

Contains all `Pin` objects supported by the board. Examples:

```
Pin.board.GP25
led = Pin(Pin.board.GP25, mode=Pin.OUT)
Pin.board.GP2.alt_list()
```

Availability: WiPy.

Constants The following constants are used to configure the pin objects. Note that not all constants are available on all ports.

`Pin.IN`

`Pin.OUT`

`Pin.OPEN_DRAIN`

`Pin.ALT`

`Pin.ALT_OPEN_DRAIN`

Selects the pin mode.

`Pin.PULL_UP`

`Pin.PULL_DOWN`

Selects the whether there is a pull up/down resistor.

`Pin.LOW_POWER`

`Pin.MED_POWER`

`Pin.HIGH_POWER`

Selects the pin drive strength.

`Pin.IRQ_FALLING`

`Pin.IRQ_RISING`

`Pin.IRQ_LOW_LEVEL`

`Pin.IRQ_HIGH_LEVEL`

Selects the IRQ trigger type.

class `RTC` – real time clock

The RTC is an independent clock that keeps track of the date and time.

Example usage:

```
rtc = machine.RTC()
rtc.init((2014, 5, 1, 4, 13, 0, 0, 0))
print(rtc.now())
```

Constructors

class `machine.RTC` (*id=0, ...*)

Create an RTC object. See `init` for parameters of initialization.

Methods

`RTC.init` (*datetime*)

Initialise the RTC. Datetime is a tuple of the form:

```
(year, month, day[, hour[, minute[, second[, microsecond[,
tzinfo]]]])
```

`RTC.now` ()

Get get the current datetime tuple.

`RTC.deinit` ()

Resets the RTC to the time of January 1, 2015 and starts running it again.

`RTC.alarm` (*id, time, /*, repeat=False*)

Set the RTC alarm. Time might be either a millisecond value to program the alarm to current time + `time_in_ms` in the future, or a datetimetuple. If the time passed is in milliseconds, `repeat` can be set to `True` to make the alarm periodic.

`RTC.alarm_left` (*alarm_id=0*)

Get the number of milliseconds left before the alarm expires.

`RTC.cancel` (*alarm_id=0*)

Cancel a running alarm.

`RTC irq` (*, *trigger, handler=None, wake=machine.IDLE*)

Create an irq object triggered by a real time clock alarm.

- `trigger` must be `RTC.ALARM0`
- `handler` is the function to be called when the callback is triggered.
- `wake` specifies the sleep mode from where this interrupt can wake up the system.

Constants

`RTC.ALARM0`

irq trigger source

class SD – secure digital memory card

The SD card class allows to configure and enable the memory card module of the WiPy and automatically mount it as `/sd` as part of the file system. There are several pin combinations that can be used to wire the SD card socket to the WiPy and the pins used can be specified in the constructor. Please check the [pinout and alternate functions table](#). for more info regarding the pins which can be remapped to be used with a SD card.

Example usage:

```
from machine import SD
import os
# clk cmd and dat0 pins must be passed along with
# their respective alternate functions
sd = machine.SD(pins=('GP10', 'GP11', 'GP15'))
os.mount(sd, '/sd')
# do normal file operations
```

Constructors

class `machine.SD(id, ...)`

Create a SD card object. See `init()` for parameters if initialization.

Methods

`SD.init(id=0, pins=('GP10', 'GP11', 'GP15'))`

Enable the SD card. In order to initialize the card, give it a 3-tuple: (`clk_pin`, `cmd_pin`, `dat0_pin`).

`SD.deinit()`

Disable the SD card.

class SPI – a master-driven serial protocol

SPI is a serial protocol that is driven by a master. At the physical level there are 3 lines: SCK, MOSI, MISO.

See usage model of I2C; SPI is very similar. Main difference is parameters to init the SPI bus:

```
from machine import SPI
spi = SPI(0, mode=SPI.MASTER, baudrate=1000000, polarity=0, phase=0, firstbit=SPI.MSB)
```

Only required parameter is `mode`, must be `SPI.MASTER`. Polarity can be 0 or 1, and is the level the idle clock line sits at. Phase can be 0 or 1 to sample data on the first or second clock edge respectively.

Constructors

class `machine.SPI(id, ...)`

Construct an SPI object on the given bus. `id` can be only 0. With no additional parameters, the SPI object is created but not initialised (it has the settings from the last initialisation of the bus, if any). If extra arguments are given, the bus is initialised. See `init` for parameters of initialisation.

Methods

`SPI.init(mode, baudrate=1000000, *, polarity=0, phase=0, bits=8, firstbit=SPI.MSB, pins=(CLK, MOSI, MISO))`

Initialise the SPI bus with the given parameters:

- `mode` must be `SPI.MASTER`.
- `baudrate` is the SCK clock rate.
- `polarity` can be 0 or 1, and is the level the idle clock line sits at.
- `phase` can be 0 or 1 to sample data on the first or second clock edge respectively.
- `bits` is the width of each transfer, accepted values are 8, 16 and 32.
- `firstbit` can be `SPI.MSB` only.
- `pins` is an optional tuple with the pins to assign to the SPI bus.

`SPI.deinit()`

Turn off the SPI bus.

`SPI.write(buf)`

Write the data contained in `buf`. Returns the number of bytes written.

`SPI.read(nbytes, *, write=0x00)`

Read the `nbytes` while writing the data specified by `write`. Return the number of bytes read.

`SPI.readinto(buf, *, write=0x00)`

Read into the buffer specified by `buf` while writing the data specified by `write`. Return the number of bytes read.

`SPI.write_readinto(write_buf, read_buf)`

Write from `write_buf` and read into `read_buf`. Both buffers must have the same length. Returns the number of bytes written

Constants

`SPI.MASTER`

for initialising the SPI bus to master

`SPI.MSB`

set the first bit to be the most significant bit

class Timer – control internal timers

Timers can be used for a great variety of tasks, calling a function periodically, counting events, and generating a PWM signal are among the most common use cases. Each timer consists of two 16-bit channels and this channels can be tied together to form one 32-bit timer. The operating mode needs to be configured per timer, but then the period (or the frequency) can be independently configured on each channel. By using the callback method, the timer event can call a Python function.

Example usage to toggle an LED at a fixed frequency:

```
from machine import Timer
from machine import Pin
led = Pin('GP16', mode=Pin.OUT)
tim = Timer(3)
tim.init(mode=Timer.PERIODIC)
tim_ch = tim.channel(Timer.A, freq=5)
tim_ch.irq(handler=lambda t:led.toggle(), trigger=Timer.TIMEOUT)
```

enable GP16 as output to drive the LED
create a timer object using timer 3
initialize it in periodic mode
configure channel A at a frequency of 5Hz
toggle a LED on every cycle

Example using named function for the callback:

```
from machine import Timer
from machine import Pin
tim = Timer(1, mode=Timer.PERIODIC, width=32)
tim_a = tim.channel(Timer.A | Timer.B, freq=1)
led = Pin('GP16', mode=Pin.OUT)

def tick(timer):
    global led
    led.toggle()

tim_a.irq(handler=tick, trigger=Timer.TIMEOUT)
```

enable GP16 as output to drive the LED
1 Hz frequency requires a 32 bit timer
we will receive the timer object when being called
toggle the LED
create the interrupt

Further examples:

```

from machine import Timer
tim1 = Timer(1, mode=Timer.ONE_SHOT) # initialize it in one shot mode
tim2 = Timer(2, mode=Timer.PWM) # initialize it in PWM mode
tim1_ch = tim1.channel(Timer.A, freq=10, polarity=Timer.POSITIVE) # start the event counter with a :
tim2_ch = tim2.channel(Timer.B, freq=10000, duty_cycle=5000) # start the PWM on channel B with
tim2_ch.freq(20) # set the frequency (can also get
tim2_ch.duty_cycle(3010) # set the duty cycle to 30.1% (ca
tim2_ch.duty_cycle(3020, Timer.NEGATIVE) # set the duty cycle to 30.2% and
tim2_ch.period(2000000) # change the period to 2 seconds

```

Note: Memory can't be allocated inside irq handlers (an interrupt) and so exceptions raised within a handler don't give much information. See `micropython.alloc_emergency_exception_buf()` for how to get around this limitation.

Constructors

`class machine.Timer(id, ...)`

Construct a new timer object of the given id. id can take values from 0 to 3.

Methods

`Timer.init(mode, *, width=16)`

Initialise the timer. Example:

```

tim.init(Timer.PERIODIC) # periodic 16-bit timer
tim.init(Timer.ONE_SHOT, width=32) # one shot 32-bit timer

```

Keyword arguments:

- mode can be one of:

- `Timer.ONE_SHOT` - The timer runs once until the configured period of the channel expires.
- `Timer.PERIODIC` - The timer runs periodically at the configured frequency of the channel.
- `Timer.PWM` - Output a PWM signal on a pin.

- width must be either 16 or 32 (bits). For really low frequencies < 5Hz (or large periods), 32-bit timers should be used. 32-bit mode is only available for `ONE_SHOT` AND `PERIODIC` modes.

`Timer.deinit()`

Deinitialises the timer. Disables all channels and associated IRQs. Stops the timer, and disables the timer peripheral.

`Timer.channel(channel, **, freq, period, polarity=Timer.POSITIVE, duty_cycle=0)`

If only a channel identifier passed, then a previously initialized channel object is returned (or `None` if there is no previous channel).

Otherwise, a `TimerChannel` object is initialized and returned.

The operating mode is is the one configured to the `Timer` object that was used to create the channel.

- channel if the width of the timer is 16-bit, then must be either `TIMER.A`, `TIMER.B`. If the width is 32-bit then it **must be** `TIMER.A | TIMER.B`.

Keyword only arguments:

- freq sets the frequency in Hz.
- period sets the period in microseconds.

Note: Either `freq` or `period` must be given, never both.

- `polarity` this is applicable for PWM, and defines the polarity of the duty cycle
- `duty_cycle` only applicable to PWM. It's a percentage (0.00-100.00). Since the WiPy doesn't support floating point numbers the duty cycle must be specified in the range 0-10000, where 10000 would represent 100.00, 5050 represents 50.50, and so on.

Note: When the channel is in PWM mode, the corresponding pin is assigned automatically, therefore there's no need to assign the alternate function of the pin via the `Pin` class. The pins which support PWM functionality are the following:

- GP24 on Timer 0 channel A.
 - GP25 on Timer 1 channel A.
 - GP9 on Timer 2 channel B.
 - GP10 on Timer 3 channel A.
 - GP11 on Timer 3 channel B.
-

class `TimerChannel` — setup a channel for a timer

Timer channels are used to generate/capture a signal using a timer.

`TimerChannel` objects are created using the `Timer.channel()` method.

Methods

`timerchannel.irq(*, trigger, priority=1, handler=None)`

The behavior of this callback is heavily dependent on the operating mode of the timer channel:

- If mode is `Timer.PERIODIC` the callback is executed periodically with the configured frequency or period.
- If mode is `Timer.ONE_SHOT` the callback is executed once when the configured timer expires.
- If mode is `Timer.PWM` the callback is executed when reaching the duty cycle value.

The accepted params are:

- `priority` level of the interrupt. Can take values in the range 1-7. Higher values represent higher priorities.
- `handler` is an optional function to be called when the interrupt is triggered.
- `trigger` must be `Timer.TIMEOUT` when the operating mode is either `Timer.PERIODIC` or `Timer.ONE_SHOT`. In the case that mode is `Timer.PWM` then `trigger` must be equal to `Timer.MATCH`.

Returns a callback object.

`timerchannel.freq([value])`

Get or set the timer channel frequency (in Hz).

`timerchannel.period([value])`

Get or set the timer channel period (in microseconds).

`timerchannel.duty_cycle([value])`

Get or set the duty cycle of the PWM signal. It's a percentage (0.00-100.00). Since the WiPy doesn't support floating point numbers the duty cycle must be specified in the range 0-10000, where 10000 would represent 100.00, 5050 represents 50.50, and so on.

Constants

`Timer.ONE_SHOT`

`Timer.PERIODIC`

`Timer.PWM`

Selects the timer operating mode.

`Timer.A`

`Timer.B`

Selects the timer channel. Must be ORed (`Timer.A | Timer.B`) when using a 32-bit timer.

`Timer.POSITIVE`

`Timer.NEGATIVE`

Timer channel polarity selection (only relevant in PWM mode).

`Timer.TIMEOUT`

`Timer.MATCH`

Timer channel IRQ triggers.

class UART – duplex serial communication bus

UART implements the standard UART/USART duplex serial communications protocol. At the physical level it consists of 2 lines: RX and TX. The unit of communication is a character (not to be confused with a string character) which can be 8 or 9 bits wide.

UART objects can be created and initialised using:

```
from machine import UART

uart = UART(1, 9600) # init with given baudrate
uart.init(9600, bits=8, parity=None, stop=1) # init with given parameters
```

Bits can be 5, 6, 7, 8. Parity can be None, `UART.EVEN` or `UART.ODD`. Stop can be 1 or 2.

A UART object acts like a stream object and reading and writing is done using the standard stream methods:

```
uart.read(10) # read 10 characters, returns a bytes object
uart.readall() # read all available characters
uart.readline() # read a line
uart.readinto(buf) # read and store into the given buffer
uart.write('abc') # write the 3 characters
```

To check if there is anything to be read, use:

```
uart.any() # returns the number of characters available for reading
```

Constructors

`class machine.UART(bus, ...)`

Construct a UART object on the given bus. `bus` can be 0 or 1. If the bus is not given, the default one will be selected (0) or the selection will be made based on the given pins.

Methods

UART.*init* (*baudrate=9600, bits=8, parity=None, stop=1, *, pins=(TX, RX, RTS, CTS)*)

Initialise the UART bus with the given parameters:

- *baudrate* is the clock rate.
- *bits* is the number of bits per character, 7, 8 or 9.
- *parity* is the parity, `None`, `UART.EVEN` or `UART.ODD`.
- *stop* is the number of stop bits, 1 or 2.
- *pins* is a 4 or 2 item list indicating the TX, RX, RTS and CTS pins (in that order). Any of the pins can be `None` if one wants the UART to operate with limited functionality. If the RTS pin is given the the RX pin must be given as well. The same applies to CTS. When no pins are given, then the default set of TX and RX pins is taken, and hardware flow control will be disabled. If *pins*=`None`, no pin assignment will be made.

UART.*deinit* ()

Turn off the UART bus.

UART.*any* ()

Return the number of characters available for reading.

UART.*read* (*[nbytes]*)

Read characters. If *nbytes* is specified then read at most that many bytes.

Return value: a bytes object containing the bytes read in. Returns `None` on timeout.

UART.*readall* ()

Read as much data as possible.

Return value: a bytes object or `None` on timeout.

UART.*readinto* (*buf*, *[nbytes]*)

Read bytes into the *buf*. If *nbytes* is specified then read at most that many bytes. Otherwise, read at most `len(buf)` bytes.

Return value: number of bytes read and stored into *buf* or `None` on timeout.

UART.*readline* ()

Read a line, ending in a newline character.

Return value: the line read or `None` on timeout.

UART.*write* (*buf*)

Write the buffer of bytes to the bus.

Return value: number of bytes written or `None` on timeout.

UART.*sendbreak* ()

Send a break condition on the bus. This drives the bus low for a duration of 13 bits. Return value: `None`.

UART.*irq* (*trigger, priority=1, handler=None, wake=machine.IDLE*)

Create a callback to be triggered when data is received on the UART.

- *trigger* can only be `UART.RX_ANY`
- *priority* level of the interrupt. Can take values in the range 1-7. Higher values represent higher priorities.
- *handler* an optional function to be called when new characters arrive.
- *wake* can only be `machine.IDLE`.

Note: The handler will be called whenever any of the following two conditions are met:

- 8 new characters have been received.
- At least 1 new character is waiting in the Rx buffer and the Rx line has been silent for the duration of 1 complete frame.

This means that when the handler function is called there will be between 1 to 8 characters waiting.

Returns an irq object.

Constants

UART.**EVEN**

UART.**ODD**

parity types (along with None)

UART.**RX_ANY**

IRQ trigger sources

class WDT – watchdog timer

The WDT is used to restart the system when the application crashes and ends up into a non recoverable state. Once started it cannot be stopped or reconfigured in any way. After enabling, the application must “feed” the watchdog periodically to prevent it from expiring and resetting the system.

Example usage:

```
from machine import WDT
wdt = WDT(timeout=2000) # enable it with a timeout of 2s
wdt.feed()
```

Constructors

class machine.**WDT** (*id=0, timeout=5000*)

Create a WDT object and start it. The timeout must be given in seconds and the minimum value that is accepted is 1 second. Once it is running the timeout cannot be changed and the WDT cannot be stopped either.

Methods

wdt.**feed**()

Feed the WDT to prevent it from resetting the system. The application should place this call in a sensible place ensuring that the WDT is only fed after verifying that everything is functioning correctly.

4.2.2 micropython – access and control MicroPython internals

Functions

micropython.**alloc_emergency_exception_buf** (*size*)

Allocate *size* bytes of RAM for the emergency exception buffer (a good size is around 100 bytes). The buffer is used to create exceptions in cases when normal RAM allocation would fail (eg within an interrupt handler) and therefore give useful traceback information in these situations.

A good way to use this function is to put it at the start of your main script (eg boot.py or main.py) and then the emergency exception buffer will be active for all the code following it.

4.2.3 network — network configuration

This module provides network drivers and routing configuration. Network drivers for specific hardware are available within this module and are used to configure a hardware network interface. Configured interfaces are then available for use via the `socket` module. To use this module the network build of firmware must be installed.

For example:

```
# configure a specific network interface
# see below for examples of specific drivers
import network
nic = network.Driver(...)
print(nic.ifconfig())

# now use socket as usual
import socket
addr = socket.getaddrinfo('micropython.org', 80)[0][-1]
s = socket.socket()
s.connect(addr)
s.send(b'GET / HTTP/1.1\r\nHost: micropython.org\r\n\r\n')
data = s.recv(1000)
s.close()
```

class Server

The `Server` class controls the behaviour and the configuration of the FTP and telnet services running on the WiPy. Any changes performed using this class' methods will affect both.

Example:

```
import network
server = network.Server()
server.deinit() # disable the server
# enable the server again with new settings
server.init(login=('user', 'password'), timeout=600)
```

Constructors

class `network.Server` (*id*, ...)

Create a server instance, see `init` for parameters of initialization.

Methods

`server.init` (*, *login*=('micro', 'python'), *timeout*=300)

Init (and effectively start the server). Optionally a new user, password and `timeout` (in seconds) can be passed.

`server.deinit` ()

Stop the server

`server.timeout` ([*timeout_in_seconds*])

Get or set the server timeout.

`server.isrunning` ()

Returns True if the server is running, False otherwise.

class WLAN

This class provides a driver for the WiFi network processor in the WiPy. Example usage:

```
import network
import time
# setup as a station
wlan = network.WLAN(mode=WLAN.STA)
wlan.connect('your-ssid', auth=(WLAN.WPA2, 'your-key'))
while not wlan.isconnected():
    time.sleep_ms(50)
print(wlan.ifconfig())

# now use socket as usual
...
```

Constructors

class `network.WLAN` (*id=0, ...*)

Create a WLAN object, and optionally configure it. See `init` for params of configuration.

Note: The `WLAN` constructor is special in the sense that if no arguments besides the `id` are given, it will return the already existing `WLAN` instance without re-configuring it. This is because `WLAN` is a system feature of the `WiPy`. If the already existing instance is not initialized it will do the same as the other constructors and will initialize it with default values.

Methods

`wlan.init` (*mode, *, ssid, auth, channel, antenna*)

Set or get the WiFi network processor configuration.

Arguments are:

- `mode` can be either `WLAN.STA` or `WLAN.AP`.
- `ssid` is a string with the ssid name. Only needed when mode is `WLAN.AP`.
- `auth` is a tuple with (sec, key). Security can be `None`, `WLAN.WEP`, `WLAN.WPA` or `WLAN.WPA2`. The key is a string with the network password. If `sec` is `WLAN.WEP` the key must be a string representing hexadecimal values (e.g. 'ABC1DE45BF'). Only needed when mode is `WLAN.AP`.
- `channel` a number in the range 1-11. Only needed when mode is `WLAN.AP`.
- `antenna` selects between the internal and the external antenna. Can be either `WLAN.INT_ANT` or `WLAN.EXT_ANT`.

For example, you can do:

```
# create and configure as an access point
wlan.init(mode=WLAN.AP, ssid='wipy-wlan', auth=(WLAN.WPA2, 'www.wipy.io'), channel=7, antenna=WLAN.EXT_ANT)
```

or:

```
# configure as a station
wlan.init(mode=WLAN.STA)
```

`wlan.connect(ssid, *, auth=None, bssid=None, timeout=None)`

Connect to a wifi access point using the given SSID, and other security parameters.

- `auth` is a tuple with (sec, key). Security can be `None`, `WLAN.WEP`, `WLAN.WPA` or `WLAN.WPA2`. The key is a string with the network password. If `sec` is `WLAN.WEP` the key must be a string representing hexadecimal values (e.g. 'ABC1DE45BF').
- `bssid` is the MAC address of the AP to connect to. Useful when there are several APs with the same ssid.
- `timeout` is the maximum time in milliseconds to wait for the connection to succeed.

`wlan.scan()`

Performs a network scan and returns a list of named tuples with (ssid, bssid, sec, channel, rssi). Note that channel is always `None` since this info is not provided by the WiPy.

`wlan.disconnect()`

Disconnect from the wifi access point.

`wlan.isconnected()`

In case of STA mode, returns `True` if connected to a wifi access point and has a valid IP address. In AP mode returns `True` when a station is connected, `False` otherwise.

`wlan.ifconfig(if_id=0, config=['dhcp' or configtuple])`

With no parameters given returns a 4-tuple of (ip, subnet_mask, gateway, DNS_server).

if 'dhcp' is passed as a parameter then the DHCP client is enabled and the IP params are negotiated with the AP.

If the 4-tuple config is given then a static IP is configured. For instance:

```
wlan.ifconfig(config=('192.168.0.4', '255.255.255.0', '192.168.0.1', '8.8.8.8'))
```

`wlan.mode(mode)`

Get or set the WLAN mode.

`wlan.ssid(ssid)`

Get or set the SSID when in AP mode.

`wlan.auth(auth)`

Get or set the authentication type when in AP mode.

`wlan.channel(channel)`

Get or set the channel (only applicable in AP mode).

`wlan.antenna(antenna)`

Get or set the antenna type (external or internal).

`wlan.mac(mac_addr)`

Get or set a 6-byte long bytes object with the MAC address.

`wlan.irq(*, handler, wake)`

Create a callback to be triggered when a WLAN event occurs during `machine.SLEEP` mode. Events are triggered by socket activity or by WLAN connection/disconnection.

- `handler` is the function that gets called when the irq is triggered.
- `wake` must be `machine.SLEEP`.

Returns an irq object.

Constants

`WLAN.STA`

`WLAN.AP`

selects the WLAN mode

`WLAN.WEP`

`WLAN.WPA`

`WLAN.WPA2`

selects the network security

`WLAN.INT_ANT`

`WLAN.EXT_ANT`

selects the antenna type

4.2.4 ctypes – access binary data in a structured way

This module implements “foreign data interface” for MicroPython. The idea behind it is similar to CPython’s `ctypes` modules, but the actual API is different, streamlined and optimized for small size. The basic idea of the module is to define data structure layout with about the same power as the C language allows, and the access it using familiar dot-syntax to reference sub-fields.

See also:

Module `struct` Standard Python way to access binary data structures (doesn’t scale well to large and complex structures).

Defining structure layout

Structure layout is defined by a “descriptor” - a Python dictionary which encodes field names as keys and other properties required to access them as associated values. Currently, `uctypes` requires explicit specification of offsets for each field. Offset are given in bytes from a structure start.

Following are encoding examples for various field types:

- Scalar types:

```
"field_name": uctypes.UINT32 | 0
```

in other words, value is scalar type identifier ORed with field offset (in bytes) from the start of the structure.

- Recursive structures:

```
"sub": (2, {
    "b0": uctypes.UINT8 | 0,
    "b1": uctypes.UINT8 | 1,
})
```

i.e. value is a 2-tuple, first element of which is offset, and second is a structure descriptor dictionary (note: offsets in recursive descriptors are relative to a structure it defines).

- Arrays of primitive types:

```
"arr": (uctypes.ARRAY | 0, uctypes.UINT8 | 2),
```

i.e. value is a 2-tuple, first element of which is ARRAY flag ORed with offset, and second is scalar element type ORed number of elements in array.

- Arrays of aggregate types:

```
"arr2": (uctypes.ARRAY | 0, 2, {"b": uctypes.UINT8 | 0}),
```

i.e. value is a 3-tuple, first element of which is ARRAY flag ORed with offset, second is a number of elements in array, and third is descriptor of element type.

- Pointer to a primitive type:

```
"ptr": (uctypes.PTR | 0, uctypes.UINT8),
```

i.e. value is a 2-tuple, first element of which is PTR flag ORed with offset, and second is scalar element type.

- Pointer to an aggregate type:

```
"ptr2": (uctypes.PTR | 0, {"b": uctypes.UINT8 | 0}),
```

i.e. value is a 2-tuple, first element of which is PTR flag ORed with offset, second is descriptor of type pointed to.

- Bitfields:

```
"bitf0": uctypes.BFUINT16 | 0 | 0 << uctypes.BF_POS | 8 << uctypes.BF_LEN,
```

i.e. value is type of scalar value containing given bitfield (typenamees are similar to scalar types, but prefixes with “BF”), ORed with offset for scalar value containing the bitfield, and further ORed with values for bit offset and bit length of the bitfield within scalar value, shifted by BF_POS and BF_LEN positions, respectively. Bitfield position is counted from the least significant bit, and is the number of right-most bit of a field (in other words, it’s a number of bits a scalar needs to be shifted right to extra the bitfield).

In the example above, first UINT16 value will be extracted at offset 0 (this detail may be important when accessing hardware registers, where particular access size and alignment are required), and then bitfield whose rightmost bit is least-significant bit of this UINT16, and length is 8 bits, will be extracted - effectively, this will access least-significant byte of UINT16.

Note that bitfield operations are independent of target byte endianness, in particular, example above will access least-significant byte of UINT16 in both little- and big-endian structures. But it depends on the least significant bit being numbered 0. Some targets may use different numbering in their native ABI, but `uctypes` always uses normalized numbering described above.

Module contents

class `uctypes.struct` (*addr, descriptor, layout_type=NATIVE*)

Instantiate a “foreign data structure” object based on structure address in memory, descriptor (encoded as a dictionary), and layout type (see below).

`uctypes.LITTLE_ENDIAN`

Layout type for a little-endian packed structure. (Packed means that every field occupies exactly as many bytes as defined in the descriptor, i.e. the alignment is 1).

`uctypes.BIG_ENDIAN`

Layout type for a big-endian packed structure.

`uctypes.NATIVE`

Layout type for a native structure - with data endianness and alignment conforming to the ABI of the system on which MicroPython runs.

`uctypes.sizeof` (*struct*)

Return size of data structure in bytes. Argument can be either structure class or specific instantiated structure object (or its aggregate field).

`uctypes.addressof(obj)`

Return address of an object. Argument should be bytes, bytearray or other object supporting buffer protocol (and address of this buffer is what actually returned).

`uctypes.bytes_at(addr, size)`

Capture memory at the given address and size as bytes object. As bytes object is immutable, memory is actually duplicated and copied into bytes object, so if memory contents change later, created object retains original value.

`uctypes.bytearray_at(addr, size)`

Capture memory at the given address and size as bytearray object. Unlike `bytes_at()` function above, memory is captured by reference, so it can be both written too, and you will access current value at the given memory address.

Structure descriptors and instantiating structure objects

Given a structure descriptor dictionary and its layout type, you can instantiate a specific structure instance at a given memory address using `uctypes.struct()` constructor. Memory address usually comes from following sources:

- Predefined address, when accessing hardware registers on a baremetal system. Lookup these addresses in datasheet for a particular MCU/SoC.
- As a return value from a call to some FFI (Foreign Function Interface) function.
- From `uctypes.addressof()`, when you want to pass arguments to an FFI function, or alternatively, to access some data for I/O (for example, data read from a file or network socket).

Structure objects

Structure objects allow accessing individual fields using standard dot notation: `my_struct.substruct1.field1`. If a field is of scalar type, getting it will produce a primitive value (Python integer or float) corresponding to the value contained in a field. A scalar field can also be assigned to.

If a field is an array, its individual elements can be accessed with the standard subscript operator `[]` - both read and assigned to.

If a field is a pointer, it can be dereferenced using `[0]` syntax (corresponding to `C *` operator, though `[0]` works in C too). Subscripting a pointer with other integer values but 0 are supported too, with the same semantics as in C.

Summing up, accessing structure fields generally follows C syntax, except for pointer dereference, when you need to use `[0]` operator instead of `*`.

Limitations

Accessing non-scalar fields leads to allocation of intermediate objects to represent them. This means that special care should be taken to layout a structure which needs to be accessed when memory allocation is disabled (e.g. from an interrupt). The recommendations are:

- Avoid nested structures. For example, instead of `mcu_registers.peripheral_a.register1`, define separate layout descriptors for each peripheral, to be accessed as `peripheral_a.register1`.
- Avoid other non-scalar data, like array. For example, instead of `peripheral_a.register[0]` use `peripheral_a.register0`.

Note that these recommendations will lead to decreased readability and conciseness of layouts, so they should be used only if the need to access structure fields without allocation is anticipated (it's even possible to define 2 parallel layouts - one for normal usage, and a restricted one to use when memory allocation is prohibited).

4.3 Libraries specific to the WiPy

The following libraries are specific to the WiPy.

4.3.1 `wipy` – WiPy specific features

The `wipy` module contains functions to control specific features of the WiPy, such as the heartbeat LED.

Functions

`wipy.heartbeat` (*[enable]*)

Get or set the state (enabled or disabled) of the heartbeat LED. Accepts and returns boolean values (`True` or `False`).

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MICROPYTHON DOCUMENTATION CONTENTS

6.1 The MicroPython language

MicroPython aims to implement the Python 3.4 standard, and most of the features of MicroPython are identical to those described by the documentation at docs.python.org.

Differences to standard Python as well as additional features of MicroPython are described in the sections here.

6.1.1 The MicroPython Interactive Interpreter Mode (aka REPL)

This section covers some characteristics of the MicroPython Interactive Interpreter Mode. A commonly used term for this is REPL (read-eval-print-loop) which will be used to refer to this interactive prompt.

Auto-indent

When typing python statements which end in a colon (for example if, for, while) then the prompt will change to three dots (...) and the cursor will be indented by 4 spaces. When you press return, the next line will continue at the same level of indentation for regular statements or an additional level of indentation where appropriate. If you press the backspace key then it will undo one level of indentation.

If your cursor is all the way back at the beginning, pressing RETURN will then execute the code that you've entered. The following shows what you'd see after entering a for statement (the underscore shows where the cursor winds up):

```
>>> for i in range(3):  
...     _
```

If you then enter an if statement, an additional level of indentation will be provided:

```
>>> for i in range(30):  
...     if i > 3:  
...         _
```

Now enter `break` followed by RETURN and press BACKSPACE:

```
>>> for i in range(30):  
...     if i > 3:  
...         break  
...     _
```

Finally type `print(i)`, press RETURN, press BACKSPACE and press RETURN again:

```
>>> for i in range(30):
...     if i > 3:
...         break
...     print(i)
...
0
1
2
3
>>>
```

Auto-indent won't be applied if the previous two lines were all spaces. This means that you can finish entering a compound statment by pressing RETURN twice, and then a third press will finish and execute.

Auto-completion

While typing a command at the REPL, if the line typed so far corresponds to the beginning of the name of something, then pressing TAB will show possible things that could be entered. For example type `m` and press TAB and it should expand to `machine`. Enter a dot `.` and press TAB again. You should see something like:

```
>>> machine.
__name__      info          unique_id     reset
bootloader    freq          rng           idle
sleep         deepsleep    disable_irq   enable_irq
Pin
```

The word will be expanded as much as possible until multiple possibilities exist. For example, type `machine.Pin.AF3` and press TAB and it will expand to `machine.Pin.AF3_TIM`. Pressing TAB a second time will show the possible expansions:

```
>>> machine.Pin.AF3_TIM
AF3_TIM10     AF3_TIM11     AF3_TIM8      AF3_TIM9
>>> machine.Pin.AF3_TIM
```

Interrupting a running program

You can interrupt a running program by pressing Ctrl-C. This will raise a `KeyboardInterrupt` which will bring you back to the REPL, providing your program doesn't intercept the `KeyboardInterrupt` exception.

For example:

```
>>> for i in range(1000000):
...     print(i)
...
0
1
2
3
...
6466
6467
6468
Traceback (most recent call last):
  File "<stdin>", line 2, in <module>
KeyboardInterrupt:
>>>
```

Paste Mode

If you want to paste some code into your terminal window, the auto-indent feature will mess things up. For example, if you had the following python code:

```
def foo():
    print('This is a test to show paste mode')
    print('Here is a second line')
foo()
```

and you try to paste this into the normal REPL, then you will see something like this:

```
>>> def foo():
...     print('This is a test to show paste mode')
...     print('Here is a second line')
...     foo()
...
File "<stdin>", line 3
IndentationError: unexpected indent
```

If you press Ctrl-E, then you will enter paste mode, which essentially turns off the auto-indent feature, and changes the prompt from >>> to ===. For example:

```
>>>
paste mode; Ctrl-C to cancel, Ctrl-D to finish
=== def foo():
===     print('This is a test to show paste mode')
===     print('Here is a second line')
=== foo()
===
This is a test to show paste mode
Here is a second line
>>>
```

Paste Mode allows blank lines to be pasted. The pasted text is compiled as if it were a file. Pressing Ctrl-D exits paste mode and initiates the compilation.

Soft Reset

A soft reset will reset the python interpreter, but tries not to reset the method by which you're connected to the MicroPython board (USB-serial, or Wifi).

You can perform a soft reset from the REPL by pressing Ctrl-D, or from your python code by executing:

```
raise SystemExit
```

For example, if you reset your MicroPython board, and you execute a dir() command, you'd see something like this:

```
>>> dir()
['__name__', 'pyb']
```

Now create some variables and repeat the dir() command:

```
>>> i = 1
>>> j = 23
>>> x = 'abc'
>>> dir()
['j', 'x', '__name__', 'pyb', 'i']
>>>
```

Now if you enter Ctrl-D, and repeat the `dir()` command, you'll see that your variables no longer exist:

```
PYB: sync filesystems
PYB: soft reboot
MicroPython v1.5-51-g6f70283-dirty on 2015-10-30; PYBv1.0 with STM32F405RG
Type "help()" for more information.
>>> dir()
['__name__', 'pyb']
>>>
```

The special variable `_` (underscore)

When you use the REPL, you may perform computations and see the results. MicroPython stores the results of the previous statement in the variable `_` (underscore). So you can use the underscore to save the result in a variable. For example:

```
>>> 1 + 2 + 3 + 4 + 5
15
>>> x = _
>>> x
15
>>>
```

Raw Mode

Raw mode is not something that a person would normally use. It is intended for programmatic use. It essentially behaves like paste mode with echo turned off.

Raw mode is entered using Ctrl-A. You then send your python code, followed by a Ctrl-D. The Ctrl-D will be acknowledged by 'OK' and then the python code will be compiled and executed. Any output (or errors) will be sent back. Entering Ctrl-B will leave raw mode and return to the regular (aka friendly) REPL.

The `tools/pyboard.py` program uses the raw REPL to execute python files on the MicroPython board.

6.1.2 Writing interrupt handlers

On suitable hardware MicroPython offers the ability to write interrupt handlers in Python. Interrupt handlers - also known as interrupt service routines (ISR's) - are defined as callback functions. These are executed in response to an event such as a timer trigger or a voltage change on a pin. Such events can occur at any point in the execution of the program code. This carries significant consequences, some specific to the MicroPython language. Others are common to all systems capable of responding to real time events. This document covers the language specific issues first, followed by a brief introduction to real time programming for those new to it.

This introduction uses vague terms like "slow" or "as fast as possible". This is deliberate, as speeds are application dependent. Acceptable durations for an ISR are dependent on the rate at which interrupts occur, the nature of the main program, and the presence of other concurrent events.

Tips and recommended practices

This summarises the points detailed below and lists the principal recommendations for interrupt handler code.

- Keep the code as short and simple as possible.
- Avoid memory allocation: no appending to lists or insertion into dictionaries, no floating point.

- Where an ISR returns multiple bytes use a pre-allocated `bytearray`. If multiple integers are to be shared between an ISR and the main program consider an array (`array.array`).
- Where data is shared between the main program and an ISR, consider disabling interrupts prior to accessing the data in the main program and re-enabling them immediately afterwards (see Critical Sections).
- Allocate an emergency exception buffer (see below).

MicroPython Issues

The emergency exception buffer

If an error occurs in an ISR, MicroPython is unable to produce an error report unless a special buffer is created for the purpose. Debugging is simplified if the following code is included in any program using interrupts.

```
import micropython
micropython.alloc_emergency_exception_buf(100)
```

Simplicity

For a variety of reasons it is important to keep ISR code as short and simple as possible. It should do only what has to be done immediately after the event which caused it: operations which can be deferred should be delegated to the main program loop. Typically an ISR will deal with the hardware device which caused the interrupt, making it ready for the next interrupt to occur. It will communicate with the main loop by updating shared data to indicate that the interrupt has occurred, and it will return. An ISR should return control to the main loop as quickly as possible. This is not a specific MicroPython issue so is covered in more detail *below*.

Communication between an ISR and the main program

Normally an ISR needs to communicate with the main program. The simplest means of doing this is via one or more shared data objects, either declared as global or shared via a class (see below). There are various restrictions and hazards around doing this, which are covered in more detail below. Integers, `bytes` and `bytearray` objects are commonly used for this purpose along with arrays (from the `array` module) which can store various data types.

The use of object methods as callbacks

MicroPython supports this powerful technique which enables an ISR to share instance variables with the underlying code. It also enables a class implementing a device driver to support multiple device instances. The following example causes two LED's to flash at different rates.

```
import pyb, micropython
micropython.alloc_emergency_exception_buf(100)
class Foo(object):
    def __init__(self, timer, led):
        self.led = led
        timer.callback(self.cb)
    def cb(self, tim):
        self.led.toggle()

red = Foo(pyb.Timer(4, freq=1), pyb.LED(1))
green = Foo(pyb.Timer(2, freq=0.8), pyb.LED(2))
```

In this example the `red` instance associates timer 4 with LED 1: when a timer 4 interrupt occurs `red.cb()` is called causing LED 1 to change state. The `green` instance operates similarly: a timer 2 interrupt results in the execution of `green.cb()` and toggles LED 2. The use of instance methods confers two benefits. Firstly a single class enables code to be shared between multiple hardware instances. Secondly, as a bound method the callback function's first argument is `self`. This enables the callback to access instance data and to save state between successive calls. For example, if the class above had a variable `self.count` set to zero in the constructor, `cb()` could increment the counter. The `red` and `green` instances would then maintain independent counts of the number of times each LED had changed state.

Creation of Python objects

ISR's cannot create instances of Python objects. This is because MicroPython needs to allocate memory for the object from a store of free memory block called the heap. This is not permitted in an interrupt handler because heap allocation is not re-entrant. In other words the interrupt might occur when the main program is part way through performing an allocation - to maintain the integrity of the heap the interpreter disallows memory allocations in ISR code.

A consequence of this is that ISR's can't use floating point arithmetic; this is because floats are Python objects. Similarly an ISR can't append an item to a list. In practice it can be hard to determine exactly which code constructs will attempt to perform memory allocation and provoke an error message: another reason for keeping ISR code short and simple.

One way to avoid this issue is for the ISR to use pre-allocated buffers. For example a class constructor creates a `bytearray` instance and a boolean flag. The ISR method assigns data to locations in the buffer and sets the flag. The memory allocation occurs in the main program code when the object is instantiated rather than in the ISR.

The MicroPython library I/O methods usually provide an option to use a pre-allocated buffer. For example `pyb.i2c.recv()` can accept a mutable buffer as its first argument: this enables its use in an ISR.

Use of Python objects

A further restriction on objects arises because of the way Python works. When an `import` statement is executed the Python code is compiled to bytecode, with one line of code typically mapping to multiple bytecodes. When the code runs the interpreter reads each bytecode and executes it as a series of machine code instructions. Given that an interrupt can occur at any time between machine code instructions, the original line of Python code may be only partially executed. Consequently a Python object such as a set, list or dictionary modified in the main loop may lack internal consistency at the moment the interrupt occurs.

A typical outcome is as follows. On rare occasions the ISR will run at the precise moment in time when the object is partially updated. When the ISR tries to read the object, a crash results. Because such problems typically occur on rare, random occasions they can be hard to diagnose. There are ways to circumvent this issue, described in *Critical Sections* below.

It is important to be clear about what constitutes the modification of an object. An alteration to a built-in type such as a dictionary is problematic. Altering the contents of an array or bytearray is not. This is because bytes or words are written as a single machine code instruction which is not interruptible: in the parlance of real time programming the write is atomic. A user defined object might instantiate an integer, array or bytearray. It is valid for both the main loop and the ISR to alter the contents of these.

MicroPython supports integers of arbitrary precision. Values between $2^{*}30 - 1$ and $-2^{*}30$ will be stored in a single machine word. Larger values are stored as Python objects. Consequently changes to long integers cannot be considered atomic. The use of long integers in ISR's is unsafe because memory allocation may be attempted as the variable's value changes.

Overcoming the float limitation

In general it is best to avoid using floats in ISR code: hardware devices normally handle integers and conversion to floats is normally done in the main loop. However there are a few DSP algorithms which require floating point. On platforms with hardware floating point (such as the Pyboard) the inline ARM Thumb assembler can be used to work round this limitation. This is because the processor stores float values in a machine word; values can be shared between the ISR and main program code via an array of floats.

Exceptions

If an ISR raises an exception it will not propagate to the main loop. The interrupt will be disabled unless the exception is handled by the ISR code.

General Issues

This is merely a brief introduction to the subject of real time programming. Beginners should note that design errors in real time programs can lead to faults which are particularly hard to diagnose. This is because they can occur rarely and at intervals which are essentially random. It is crucial to get the initial design right and to anticipate issues before they arise. Both interrupt handlers and the main program need to be designed with an appreciation of the following issues.

Interrupt Handler Design

As mentioned above, ISR's should be designed to be as simple as possible. They should always return in a short, predictable period of time. This is important because when the ISR is running, the main loop is not: inevitably the main loop experiences pauses in its execution at random points in the code. Such pauses can be a source of hard to diagnose bugs particularly if their duration is long or variable. In order to understand the implications of ISR run time, a basic grasp of interrupt priorities is required.

Interrupts are organised according to a priority scheme. ISR code may itself be interrupted by a higher priority interrupt. This has implications if the two interrupts share data (see Critical Sections below). If such an interrupt occurs it interposes a delay into the ISR code. If a lower priority interrupt occurs while the ISR is running, it will be delayed until the ISR is complete: if the delay is too long, the lower priority interrupt may fail. A further issue with slow ISR's is the case where a second interrupt of the same type occurs during its execution. The second interrupt will be handled on termination of the first. However if the rate of incoming interrupts consistently exceeds the capacity of the ISR to service them the outcome will not be a happy one.

Consequently looping constructs should be avoided or minimised. I/O to devices other than to the interrupting device should normally be avoided: I/O such as disk access, `print` statements and UART access is relatively slow, and its duration may vary. A further issue here is that filesystem functions are not reentrant: using filesystem I/O in an ISR and the main program would be hazardous. Crucially ISR code should not wait on an event. I/O is acceptable if the code can be guaranteed to return in a predictable period, for example toggling a pin or LED. Accessing the interrupting device via I2C or SPI may be necessary but the time taken for such accesses should be calculated or measured and its impact on the application assessed.

There is usually a need to share data between the ISR and the main loop. This may be done either through global variables or via class or instance variables. Variables are typically integer or boolean types, or integer or byte arrays (a pre-allocated integer array offers faster access than a list). Where multiple values are modified by the ISR it is necessary to consider the case where the interrupt occurs at a time when the main program has accessed some, but not all, of the values. This can lead to inconsistencies.

Consider the following design. An ISR stores incoming data in a bytearray, then adds the number of bytes received to an integer representing total bytes ready for processing. The main program reads the number of bytes, processes the

bytes, then clears down the number of bytes ready. This will work until an interrupt occurs just after the main program has read the number of bytes. The ISR puts the added data into the buffer and updates the number received, but the main program has already read the number, so processes the data originally received. The newly arrived bytes are lost.

There are various ways of avoiding this hazard, the simplest being to use a circular buffer. If it is not possible to use a structure with inherent thread safety other ways are described below.

Reentrancy

A potential hazard may occur if a function or method is shared between the main program and one or more ISR's or between multiple ISR's. The issue here is that the function may itself be interrupted and a further instance of that function run. If this is to occur, the function must be designed to be reentrant. How this is done is an advanced topic beyond the scope of this tutorial.

Critical Sections

An example of a critical section of code is one which accesses more than one variable which can be affected by an ISR. If the interrupt happens to occur between accesses to the individual variables, their values will be inconsistent. This is an instance of a hazard known as a race condition: the ISR and the main program loop race to alter the variables. To avoid inconsistency a means must be employed to ensure that the ISR does not alter the values for the duration of the critical section. One way to achieve this is to issue `pyb.disable_irq()` before the start of the section, and `pyb.enable_irq()` at the end. Here is an example of this approach:

```
import pyb, micropython, array
micropython.alloc_emergency_exception_buf(100)

class BoundsException(Exception):
    pass

ARRAYSIZE = const(20)
index = 0
data = array.array('i', 0 for x in range(ARRAYSIZE))

def callback1(t):
    global data, index
    for x in range(5):
        data[index] = pyb.rng() # simulate input
        index += 1
        if index >= ARRAYSIZE:
            raise BoundsException('Array bounds exceeded')

tim4 = pyb.Timer(4, freq=100, callback=callback1)

for loop in range(1000):
    if index > 0:
        irq_state = pyb.disable_irq() # Start of critical section
        for x in range(index):
            print(data[x])
        index = 0
        pyb.enable_irq(irq_state) # End of critical section
        print('loop {}'.format(loop))
    pyb.delay(1)

tim4.callback(None)
```

A critical section can comprise a single line of code and a single variable. Consider the following code fragment.

```

count = 0
def cb(): # An interrupt callback
    count +=1
def main():
    # Code to set up the interrupt callback omitted
    while True:
        count += 1

```

This example illustrates a subtle source of bugs. The line `count += 1` in the main loop carries a specific race condition hazard known as a read-modify-write. This is a classic cause of bugs in real time systems. In the main loop MicroPython reads the value of `t.counter`, adds 1 to it, and writes it back. On rare occasions the interrupt occurs after the read and before the write. The interrupt modifies `t.counter` but its change is overwritten by the main loop when the ISR returns. In a real system this could lead to rare, unpredictable failures.

As mentioned above, care should be taken if an instance of a Python built in type is modified in the main code and that instance is accessed in an ISR. The code performing the modification should be regarded as a critical section to ensure that the instance is in a valid state when the ISR runs.

Particular care needs to be taken if a dataset is shared between different ISR's. The hazard here is that the higher priority interrupt may occur when the lower priority one has partially updated the shared data. Dealing with this situation is an advanced topic beyond the scope of this introduction other than to note that mutex objects described below can sometimes be used.

Disabling interrupts for the duration of a critical section is the usual and simplest way to proceed, but it disables all interrupts rather than merely the one with the potential to cause problems. It is generally undesirable to disable an interrupt for long. In the case of timer interrupts it introduces variability to the time when a callback occurs. In the case of device interrupts, it can lead to the device being serviced too late with possible loss of data or overrun errors in the device hardware. Like ISR's, a critical section in the main code should have a short, predictable duration.

An approach to dealing with critical sections which radically reduces the time for which interrupts are disabled is to use an object termed a mutex (name derived from the notion of mutual exclusion). The main program locks the mutex before running the critical section and unlocks it at the end. The ISR tests whether the mutex is locked. If it is, it avoids the critical section and returns. The design challenge is defining what the ISR should do in the event that access to the critical variables is denied. A simple example of a mutex may be found [here](#). Note that the mutex code does disable interrupts, but only for the duration of eight machine instructions: the benefit of this approach is that other interrupts are virtually unaffected.

6.1.3 Maximising Python Speed

This tutorial describes ways of improving the performance of MicroPython code. Optimisations involving other languages are covered elsewhere, namely the use of modules written in C and the MicroPython inline ARM Thumb-2 assembler.

The process of developing high performance code comprises the following stages which should be performed in the order listed.

- Design for speed.
- Code and debug.

Optimisation steps:

- Identify the slowest section of code.
- Improve the efficiency of the Python code.
- Use the native code emitter.
- Use the viper code emitter.

Designing for speed

Performance issues should be considered at the outset. This involves taking a view on the sections of code which are most performance critical and devoting particular attention to their design. The process of optimisation begins when the code has been tested: if the design is correct at the outset optimisation will be straightforward and may actually be unnecessary.

Algorithms

The most important aspect of designing any routine for performance is ensuring that the best algorithm is employed. This is a topic for textbooks rather than for a MicroPython guide but spectacular performance gains can sometimes be achieved by adopting algorithms known for their efficiency.

RAM Allocation

To design efficient MicroPython code it is necessary to have an understanding of the way the interpreter allocates RAM. When an object is created or grows in size (for example where an item is appended to a list) the necessary RAM is allocated from a block known as the heap. This takes a significant amount of time; further it will on occasion trigger a process known as garbage collection which can take several milliseconds.

Consequently the performance of a function or method can be improved if an object is created once only and not permitted to grow in size. This implies that the object persists for the duration of its use: typically it will be instantiated in a class constructor and used in various methods.

This is covered in further detail *Controlling garbage collection* below.

Buffers

An example of the above is the common case where a buffer is required, such as one used for communication with a device. A typical driver will create the buffer in the constructor and use it in its I/O methods which will be called repeatedly.

The MicroPython libraries typically provide support for pre-allocated buffers. For example, objects which support stream interface (e.g., file or UART) provide `read()` method which allocate new buffer for read data, but also a `readinto()` method to read data into an existing buffer.

Floating Point

Some MicroPython ports allocate floating point numbers on heap. Some other ports may lack dedicated floating-point coprocessor, and perform arithmetic operations on them in “software” at considerably lower speed than on integers. Where performance is important, use integer operations and restrict the use of floating point to sections of the code where performance is not paramount. For example, capture ADC readings as integers values to an array in one quick go, and only then convert them to floating-point numbers for signal processing.

Arrays

Consider the use of the various types of array classes as an alternative to lists. The `array` module supports various element types with 8-bit elements supported by Python’s built in `bytes` and `bytearray` classes. These data structures all store elements in contiguous memory locations. Once again to avoid memory allocation in critical code these should be pre-allocated and passed as arguments or as bound objects.

When passing slices of objects such as `bytearray` instances, Python creates a copy which involves allocation of the size proportional to the size of slice. This can be alleviated using a `memoryview` object. `memoryview` itself is allocated on heap, but is a small, fixed-size object, regardless of the size of slice it points too.

```
ba = bytearray(10000) # big array
func(ba[30:2000])   # a copy is passed, ~2K new allocation
mv = memoryview(ba) # small object is allocated
func(mv[30:2000])   # a pointer to memory is passed
```

A `memoryview` can only be applied to objects supporting the buffer protocol - this includes arrays but not lists. Small caveat is that while `memoryview` object is live, it also keeps alive the original buffer object. So, a `memoryview` isn't a universal panacea. For instance, in the example above, if you are done with 10K buffer and just need those bytes 30:2000 from it, it may be better to make a slice, and let the 10K buffer go (be ready for garbage collection), instead of making a long-living `memoryview` and keeping 10K blocked for GC.

Nonetheless, `memoryview` is indispensable for advanced preallocated buffer management. `.readinto()` method discussed above puts data at the beginning of buffer and fills in entire buffer. What if you need to put data in the middle of existing buffer? Just create a `memoryview` into the needed section of buffer and pass it to `.readinto()`.

Identifying the slowest section of code

This is a process known as profiling and is covered in textbooks and (for standard Python) supported by various software tools. For the type of smaller embedded application likely to be running on MicroPython platforms the slowest function or method can usually be established by judicious use of the timing `ticks` group of functions documented [here](#). Code execution time can be measured in ms, us, or CPU cycles.

The following enables any function or method to be timed by adding an `@timed_function` decorator:

```
def timed_function(f, *args, **kwargs):
    myname = str(f).split(' ')[1]
    def new_func(*args, **kwargs):
        t = time.ticks_us()
        result = f(*args, **kwargs)
        delta = time.ticks_diff(t, time.ticks_us())
        print('Function {} Time = {:.6.3f}ms'.format(myname, delta/1000))
        return result
    return new_func
```

MicroPython code improvements

The `const()` declaration

MicroPython provides a `const()` declaration. This works in a similar way to `#define` in C in that when the code is compiled to bytecode the compiler substitutes the numeric value for the identifier. This avoids a dictionary lookup at runtime. The argument to `const()` may be anything which, at compile time, evaluates to an integer e.g. `0x100` or `1 << 8`.

Caching object references

Where a function or method repeatedly accesses objects performance is improved by caching the object in a local variable:

```
class foo(object):
    def __init__(self):
        ba = bytearray(100)
    def bar(self, obj_display):
        ba_ref = self.ba
        fb = obj_display.framebuffer
        # iterative code using these two objects
```

This avoids the need repeatedly to look up `self.ba` and `obj_display.framebuffer` in the body of the method `bar()`.

Controlling garbage collection

When memory allocation is required, MicroPython attempts to locate an adequately sized block on the heap. This may fail, usually because the heap is cluttered with objects which are no longer referenced by code. If a failure occurs, the process known as garbage collection reclaims the memory used by these redundant objects and the allocation is then tried again - a process which can take several milliseconds.

There are benefits in pre-empting this by periodically issuing `gc.collect()`. Firstly doing a collection before it is actually required is quicker - typically on the order of 1ms if done frequently. Secondly you can determine the point in code where this time is used rather than have a longer delay occur at random points, possibly in a speed critical section. Finally performing collections regularly can reduce fragmentation in the heap. Severe fragmentation can lead to non-recoverable allocation failures.

Accessing hardware directly

This comes into the category of more advanced programming and involves some knowledge of the target MCU. Consider the example of toggling an output pin on the Pyboard. The standard approach would be to write

```
mypin.value(mypin.value() ^ 1) # mypin was instantiated as an output pin
```

This involves the overhead of two calls to the `Pin` instance's `value()` method. This overhead can be eliminated by performing a read/write to the relevant bit of the chip's GPIO port output data register (`odr`). To facilitate this the `stm` module provides a set of constants providing the addresses of the relevant registers. A fast toggle of pin P4 (CPU pin A14) - corresponding to the green LED - can be performed as follows:

```
BIT14 = const(1 << 14)
stm.mem16[stm.GPIOA + stm.GPIO_ODR] ^= BIT14
```

The Native code emitter

This causes the MicroPython compiler to emit ARM native opcodes rather than bytecode. It covers the bulk of the Python language so most functions will require no adaptation (but see below). It is invoked by means of a function decorator:

```
@micropython.native
def foo(self, arg):
    buf = self.linebuf # Cached object
    # code
```

There are certain limitations in the current implementation of the native code emitter.

- Context managers are not supported (the `with` statement).
- Generators are not supported.

- If `raise` is used an argument must be supplied.

The trade-off for the improved performance (roughly twice as fast as bytecode) is an increase in compiled code size.

The Viper code emitter

The optimisations discussed above involve standards-compliant Python code. The Viper code emitter is not fully compliant. It supports special Viper native data types in pursuit of performance. Integer processing is non-compliant because it uses machine words: arithmetic on 32 bit hardware is performed modulo 2^{**32} .

Like the Native emitter Viper produces machine instructions but further optimisations are performed, substantially increasing performance especially for integer arithmetic and bit manipulations. It is invoked using a decorator:

```
@micropython.viper
def foo(self, arg: int) -> int:
    # code
```

As the above fragment illustrates it is beneficial to use Python type hints to assist the Viper optimiser. Type hints provide information on the data types of arguments and of the return value; these are a standard Python language feature formally defined here [PEP0484](#). Viper supports its own set of types namely `int`, `uint` (unsigned integer), `ptr`, `ptr8`, `ptr16` and `ptr32`. The `ptrX` types are discussed below. Currently the `uint` type serves a single purpose: as a type hint for a function return value. If such a function returns `0xffffffff` Python will interpret the result as $2^{**32} - 1$ rather than as `-1`.

In addition to the restrictions imposed by the native emitter the following constraints apply:

- Functions may have up to four arguments.
- Default argument values are not permitted.
- Floating point may be used but is not optimised.

Viper provides pointer types to assist the optimiser. These comprise

- `ptr` Pointer to an object.
- `ptr8` Points to a byte.
- `ptr16` Points to a 16 bit half-word.
- `ptr32` Points to a 32 bit machine word.

The concept of a pointer may be unfamiliar to Python programmers. It has similarities to a Python `memoryview` object in that it provides direct access to data stored in memory. Items are accessed using subscript notation, but slices are not supported: a pointer can return a single item only. Its purpose is to provide fast random access to data stored in contiguous memory locations - such as data stored in objects which support the buffer protocol, and memory-mapped peripheral registers in a microcontroller. It should be noted that programming using pointers is hazardous: bounds checking is not performed and the compiler does nothing to prevent buffer overrun errors.

Typical usage is to cache variables:

```
@micropython.viper
def foo(self, arg: int) -> int:
    buf = ptr8(self.linebuf) # self.linebuf is a bytearray or bytes object
    for x in range(20, 30):
        bar = buf[x] # Access a data item through the pointer
    # code omitted
```

In this instance the compiler “knows” that `buf` is the address of an array of bytes; it can emit code to rapidly compute the address of `buf[x]` at runtime. Where casts are used to convert objects to Viper native types these should be performed at the start of the function rather than in critical timing loops as the cast operation can take several microseconds. The rules for casting are as follows:

- Casting operators are currently: `int`, `bool`, `uint`, `ptr`, `ptr8`, `ptr16` and `ptr32`.
- The result of a cast will be a native Viper variable.
- Arguments to a cast can be a Python object or a native Viper variable.
- If argument is a native Viper variable, then cast is a no-op (i.e. costs nothing at runtime) that just changes the type (e.g. from `uint` to `ptr8`) so that you can then store/load using this pointer.
- If the argument is a Python object and the cast is `int` or `uint`, then the Python object must be of integral type and the value of that integral object is returned.
- The argument to a `bool` cast must be integral type (boolean or integer); when used as a return type the viper function will return `True` or `False` objects.
- If the argument is a Python object and the cast is `ptr`, `ptr8`, `ptr16` or `ptr32`, then the Python object must either have the buffer protocol with read-write capabilities (in which case a pointer to the start of the buffer is returned) or it must be of integral type (in which case the value of that integral object is returned).

The following example illustrates the use of a `ptr16` cast to toggle pin X1 `n` times:

```
BIT0 = const(1)
@micropython.viper
def toggle_n(n: int):
    odr = ptr16(stm.GPIOA + stm.GPIO_ODR)
    for _ in range(n):
        odr[0] ^= BIT0
```

A detailed technical description of the three code emitters may be found on Kickstarter here [Note 1](#) and here [Note 2](#)

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