
canberry Documentation

Release 0.4

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A small web app that displays sensor data and controls a [MOVIDRIVE Antriebsumrichter](#) (traction converter) of SEW EURODRIVE connected to the [Raspberry Pi](#) with the help of a controller area network (CAN) bus.

- [MOVIDRIVE Serielle Kommunikation \(10531602\)](#)
- [MOVIDRIVE Handbuch \(09191607\)](#)
- [MOVIDRIVE Betriebsanleitung \(10532609\)](#)
- [MOVIDRIVE Operating Instruction \(10532617\)](#)

Installation

In order to install CANberry just create a virtual environment and use pip:

```
pip install canberry
```

Configuration

Create a configuration file `.canrc` with following content in your home directory:

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

[canberry]
identifier = 16
```

The identifier is the default target address.

Development

Installation:

- Create a virtual environment *virtualenv venv* and activate it with *source venv/bin/activate*.
- Install all dependencies with *pip install -r requirements.txt*.
- Run *python setup.py develop* to install CANberry in your virtual environment.
- Run *canberry* from the command line to start the web application. Try *canberry -h* for help on more options.

Updating the javascript components with:

- Install *npm* with *sudo apt-get install nodejs*.
- Install *bower* with *sudo npm install -g bower*.
- Use *bower install -S* to install and update js dependencies like concise, ractive, jquery, flotcharts.

Credits

This project uses following libraries:

- [jQuery](#)
- [Concise CSS](#)
- [Ractive.js](#)
- [Flot](#)
- [python-can](#)

Note

This project has been set up using PyScaffold. For details and usage information on PyScaffold see <http://pyscaffold.readthedocs.org/>.

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Changelog

Version 0.3

- Sending data is possible via the WebUI

Version 0.2

- Removed python-can contrib again
- Extended the documentation

Version 0.1.1

- Attempt to fix the python-can imports

Version 0.1

- First beta-like release

Indices and tables

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- [modindex](#)
- [search](#)