

RobotFramework_UDS

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Chapter 1

Introduction

The library **RobotFramework-UDS** provides a set of **Robot Framework** keywords for sending UDS (Unified Diagnostic Services) requests and interpreting responses from automotive electronic control units (ECUs).

Whether you're testing diagnostic sessions, reading data, or controlling routines on an ECU, the UDS Library simplifies these tasks by offering specific keywords like `DiagnosticSessionControl`, `ReadDataByIdentifier`, and `RoutineControl`.

These keywords are designed to handle the complexity of UDS communication, enabling you to write efficient and reliable automated tests.

Moreover, you can now refer to UDS services by their readable names rather than hexadecimal IDs e.g `ReadDataByName`, `RoutineControlByName`. It helps to make your tests more intuitive and easier to maintain.

Chapter 2

Description

2.1 Overview

The **RobotFramework-UDS** is designed to interface with automotive ECUs using the UDS protocol over the DoIP (Diagnostic over IP) transport layer. This library abstracts the complexities of UDS communication, allowing users to focus on writing high-level test cases that validate specific diagnostic services and responses.

2.2 UDS Connector (DoIP)

Currently, the library supports the **DoIP** (Diagnostic over IP) transport layer, which is commonly used in modern vehicles for diagnostic communication. DoIP allows for faster data transfer rates and easier integration with network-based systems compared to traditional CAN-based diagnostics.

2.3 Configuration

In order to connect and send/receive message properly using the **RobotFramework-UDS** certain configurations must be set up:

- **DoIP Configuration:** The library requires the IP address and port of the ECU or the gateway through which the ECU is accessed.
- **Data Identifiers and Codec:** Define the Data Identifiers (DIDs) and corresponding codecs in the library's configuration. This enables correct encoding and decoding of data between the test cases and the ECU.
- **Session Management:** Some UDS services may require the ECU to be in a specific diagnostic session (e.g., extended diagnostics). The library should be configured to manage these session transitions seamlessly.

2.4 Supported UDS Services

The **RobotFramework-UDS** library supports almost UDS service as defined in [ISO 14229](#), providing comprehensive coverage for ECU diagnostics.

For detailed information on specific services and how to use them, please refer to the next section.

2.5 Enhancements Usability with ODXTools Integration

The **RobotFramework-UDS** library comes with [odxtools](#) fully integrated, allowing you to use readable service names instead of dealing with hex IDs.

You can now specify service names directly in your test cases, making them more readable and user-friendly.

The **RobotFramework-UDS** also supports automatic data type conversion for request parameters, enabling users to provide input values that are seamlessly converted into the correct data types required for UDS requests.

The **RobotFramework-UDS** library supports features such as Routine Control By Name, Read Data By Name, and Write Data By Name, enabling users to send requests to UDS using the service's name instead of its identifier.

The **RobotFramework-UDS** provides a versatile "Send UDS Request By Name" keyword that can send and receive UDS messages without requiring the command type specification (e.g., Read, Write, RoutineControl). This allows users to send requests without needing to know the specific UDS command type associated with a service, as the keyword automatically detects and handles it.

Examples

Send UDS Request By Name

```

Test user can send UDS request without needing to specify the command type
  Log    Test user can send UDS request without needing to specify the command type

  Log    readCPUClockFrequencies_Read
  ${service_name_list}=    Create List    readCPUClockFrequencies_Read
  ${responses}=    Send UDS Request By Name    ${service_name_list}
  Log    ${responses}    console=True

  FOR    ${request_id}    IN    @${responses.keys()}
    Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
    ${response}=    Set Variable    ${responses["${request_id}"]}
    FOR    ${item}    IN    @${response.keys()}
      Log    ${item} : ${response["${item}"]}    console=True
    END
  END

  Log    CAM1PowerSupply_Set
  ${param_dict_input_output_control}=    Create Dictionary    mode=passiv
  ${response}=    Send UDS Request By Name    CAM1PowerSupply_Set    ${←
  ← param_dict_input_output_control}

  Log    ${response}    console=True
  FOR    ${item}    IN    @${response.keys()}
    Log    ${item} : ${response["${item}"]}    console=True
  END

  Log    RealTimeClock_Write
  ${param_dict_write_data_by_name}=    Create Dictionary    Day=26    Month=September    ←
  ← Year=2024    Hour=10    Second=45    Minute=0
  ${res}=    Send UDS Request By Name    RealTimeClock_Write    ${←
  ← param_dict_write_data_by_name}
  Log    ${res}    console=True

  Log    Routine Control By Name service: StartIperfServer_Start

  ${param_dict_routine_control_by_name}=    Create Dictionary    port=5101    argument=←
  ← -i 0.5 -B 192.168.1.
  ${response}=    Send UDS Request By Name    StartIperfServer_Start    ${←
  ← param_dict_routine_control_by_name}

  Log    ${response}    console=True
  FOR    ${item}    IN    @${response.keys()}
    Log    ${item} : ${response["${item}"]}    console=True
  END

```

Routine Control By Name

```

Test user can use Routine Control By Name service on ECU
  Log    Routine Control By Name service: StartIperfServer_Start

  ${param_dict}=    Create Dictionary    port=5101    argument=-i 0.5 -B 192.168.1.
  ${response}=    Routine Control By Name    StartIperfServer_Start    ${param_dict}

  Log    ${response}    console=True
  FOR    ${item}    IN    @${response.keys()}
    Log    ${item} : ${response["${item}"]}    console=True
  END

```

Read Data By Name

```

Test user can use Read Data By Name service on ECU
Log    Use Read Data By Name service

Log    Use Read Data By Identifier - 25392

${list_identifiers}=    Create List    0x6330
${res}=    Read Data By Identifier    ${list_identifiers}
Log    ${res}    console=True
Log    ${res[0x6330]}    console=True

Log    readCPUClockFrequencies_Read

${service_name_list}=    Create List    readCPUClockFrequencies_Read
${responses}=    Read Data By Name    ${service_name_list}
Log    ${responses}    console=True

FOR    ${request_id}    IN    @${responses.keys()}
Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
${response}=    Set Variable    ${responses["${request_id}"]}
FOR    ${item}    IN    @${response.keys()}
Log    ${item} : ${response["${item}"]}    console=True
END
END

Test Read List Services
${list_read_services}=    Create List    TestManager_SWVersion_Read
...                        CTSSWVersion_Read
...                        CPU_Load_Read

FOR    ${service_name}    IN    @${list_read_services}
Log    Read Data of ${service_name}    console=True
${list_service}=    Create List    ${service_name}
${res}=    Read Data By Name    ${list_service}
Log    ${res}    console=True
END

```

Write Data By Name

```

Test user can use Write Data By Name service on ECU
Log    Write Data By Name service

Log    RealTimeClock_Write
${PARAM_DICT}=    Create Dictionary    Day=26    Month=September    Year=2024    Hour↔
↔ =10    Second=45    Minute=0
${res}=    Write Data By Name    RealTimeClock_Write    ${PARAM_DICT}
Log    ${res}    console=True

${DICT}=    Create Dictionary    ipAddress=155
${res}=    Write Data By Name    CTS_IPAddress_Write    ${DICT}
Log    ${res}    console=True

Log    Using service did instead service's name
${res}=    Write Data By Identifier    25382    ${PARAM_DICT}
Log    ${res}    console=True

```

2.6 Multiple Connections

The **RobotFramework-UDS** can be extended to manage multiple connections simultaneously. This is beneficial when working with complex vehicle systems or simultaneously testing multiple ECUs.

2.7 Examples

Single Connection

```

*** Settings ***
Library      RobotFramework_TestsuitesManagement    AS    testsuites
Library      RobotFramework_UDS

*** Variables ***
${SUT_IP_ADDRESS}=          SUT_IP_ADDRESS
${SUT_LOGICAL_ADDRESS}=    SUT_LOGICAL_ADDRESS
${TB_IP_ADDRESS}=          TB_IP_ADDRESS
${TB_LOGICAL_ADDRESS}=    TB_LOGICAL_ADDRESS
${ACTIVATION_TYPE}=        0
${DEVICE_NAME_1}=          UDS Connector 1
${FILE_1}=                  path/file.pdx
${VARIANT_1}=              variant

*** Test Cases ***
Test user can connect single UDS connection
    Log      Test user can connect single UDS connection
    Log      If no device_name is provided, it will default to 'default'

    Create UDS Connector    ecu_ip_address= ${SUT_IP_ADDRESS_1}
    ...                    ecu_logical_address= ${SUT_LOGICAL_ADDRESS_1}
    ...                    client_ip_address= ${TB_IP_ADDRESS_1}
    ...                    client_logical_address= ${TB_LOGICAL_ADDRESS_1}
    ...                    activation_type= ${ACTIVATION_TYPE_1}

    Connect UDS Connector
    Open UDS Connection
    Load PDX    ${FILE_1}    ${VARIANT_1}
    ${service_name_list}=    Create List    readCPUClockFrequencies_Read
    Read Data By Name    ${service_name_list}
    Close UDS Connection

```

Multiple Connections

```

*** Variables ***
${SUT_IP_ADDRESS_1}=          SUT_IP_ADDRESS_1
${SUT_LOGICAL_ADDRESS_1}=    SUT_LOGICAL_ADDRESS_1
${TB_IP_ADDRESS_1}=          TB_IP_ADDRESS_1
${TB_LOGICAL_ADDRESS_1}=    TB_LOGICAL_ADDRESS_1
${ACTIVATION_TYPE_1}=        0
${DEVICE_NAME_1}=          UDS Connector 1
${FILE_1}=                  path/file_1.pdx
${VARIANT_1}=              VARIANT_1

${SUT_IP_ADDRESS_2}=          SUT_IP_ADDRESS_2
${SUT_LOGICAL_ADDRESS_2}=    SUT_LOGICAL_ADDRESS_2
${TB_IP_ADDRESS_2}=          TB_IP_ADDRESS_2
${TB_LOGICAL_ADDRESS_2}=    TB_LOGICAL_ADDRESS_2
${ACTIVATION_TYPE_2}=        0
${DEVICE_NAME_2}=          UDS Connector 2
${FILE_2}=                  path/file_2.pdx
${VARIANT_2}=              VARIANT_2

${ERROR_STR}=    NegativeResponseException: ReadDataByIdentifier service execution ↔
    ↔ returned a negative response IncorrectMessageLengthOrInvalidFormat (0x13)

*** Test Cases ***
Test user can connect multiple UDS connection
    Log      Test user can connect multiple UDS connection
    Log      Connect to device 1
    Create UDS Connector    device_name= ${DEVICE_NAME_1}
    ...                    ecu_ip_address= ${SUT_IP_ADDRESS_1}
    ...                    ecu_logical_address= ${SUT_LOGICAL_ADDRESS_1}
    ...                    client_ip_address= ${TB_IP_ADDRESS_1}

```

```

...          client_logical_address= ${TB_LOGICAL_ADDRESS_1}
...          activation_type= ${ACTIVATION_TYPE_1}
Connect UDS Connector  device_name= ${DEVICE_NAME_1}

Open UDS Connection  device_name= ${DEVICE_NAME_1}
Load PDX  ${FILE_1}  ${VARIANT_1}  device_name= ${DEVICE_NAME_1}
${service_name_list_1}=  Create List  readCPUClockFrequencies_Read
Read Data By Name  ${service_name_list_1}  device_name= ${DEVICE_NAME_1}

Log  Connect to device 2
Create UDS Connector  device_name= ${DEVICE_NAME_2}
...          ecu_ip_address= ${SUT_IP_ADDRESS_2}
...          ecu_logical_address= ${SUT_LOGICAL_ADDRESS_2}
...          client_ip_address= ${TB_IP_ADDRESS_2}
...          client_logical_address= ${TB_LOGICAL_ADDRESS_2}
...          activation_type= ${ACTIVATION_TYPE_2}
Connect UDS Connector  device_name= ${DEVICE_NAME_2}

Open UDS Connection  device_name= ${DEVICE_NAME_2}
Load PDX  ${FILE_2}  ${VARIANT_2}  device_name= ${DEVICE_NAME_2}
${service_name_list_2}=  Create List  CPUload_Read
Log  Expected device 2 cannot send readCPUClockFrequencies_Read service like device←
↵ 1
Run Keyword And Expect Error  ${ERROR_STR}  Read Data By Name  ${↵
↵ service_name_list_1}  device_name= ${DEVICE_NAME_2}

Read Data By Name  ${service_name_list_2}  device_name= ${DEVICE_NAME_2}

Test user can connect multiple UDS connection but connect to the same ECU
Log  Test user can connect multiple UDS connection
Log  Connect to device 1
Create UDS Connector  device_name= ${DEVICE_NAME_1}
...          ecu_ip_address= ${SUT_IP_ADDRESS_1}
...          ecu_logical_address= ${SUT_LOGICAL_ADDRESS_1}
...          client_ip_address= ${TB_IP_ADDRESS_1}
...          client_logical_address= ${TB_LOGICAL_ADDRESS_1}
...          activation_type= ${ACTIVATION_TYPE_1}
Connect UDS Connector  device_name= ${DEVICE_NAME_1}

Log  Open uds connection
Open UDS Connection  device_name= ${DEVICE_NAME_1}
Load PDX  ${FILE_1}  ${VARIANT_1}  device_name= ${DEVICE_NAME_1}
${service_name_list_1}=  Create List  readCPUClockFrequencies_Read
Read Data By Name  ${service_name_list_1}  device_name= ${DEVICE_NAME_1}

Log  Connect to device 2 but same IP as device 1
Log  The expected test case result in an error
Run Keyword And Expect Error  TimeoutError: ECU failed to respond in time  Create↵
↵ UDS Connector  device_name= ${DEVICE_NAME_2}
...          ↵
↵          ecu_ip_address= ${SUT_IP_ADDRESS_1}
...          ↵
↵          ecu_logical_address= ${SUT_LOGICAL_ADDRESS_1}
...          ↵
↵          client_ip_address= ${TB_IP_ADDRESS_1}
...          ↵
↵          client_logical_address= ${TB_LOGICAL_ADDRESS_1}
...          ↵
↵          activation_type= ${ACTIVATION_TYPE_1}

Test users can reconnect to the closed ECU
Log  Connect to device 2
Create UDS Connector  device_name= ${DEVICE_NAME_2}
...          ecu_ip_address= ${SUT_IP_ADDRESS_2}
...          ecu_logical_address= ${SUT_LOGICAL_ADDRESS_2}
...          client_ip_address= ${TB_IP_ADDRESS_2}
...          client_logical_address= ${TB_LOGICAL_ADDRESS_2}
...          activation_type= ${ACTIVATION_TYPE_1}

```

```

Connect UDS Connector      device_name= ${DEVICE_NAME_2}

Open UDS Connection      device_name= ${DEVICE_NAME_2}
Load PDX      ${FILE_2}      ${VARIANT_2}      device_name= ${DEVICE_NAME_2}
${service_name_list_2}=   Create List      CPUload_Read
Read Data By Name      ${service_name_list_2}      device_name= ${DEVICE_NAME_2}
Close UDS Connection      device_name= ${DEVICE_NAME_2}

Log      Connect to device 1
Create UDS Connector      device_name= ${DEVICE_NAME_1}
...
...      ecu_ip_address= ${SUT_IP_ADDRESS_1}
...      ecu_logical_address= ${SUT_LOGICAL_ADDRESS_1}
...      client_ip_address= ${TB_IP_ADDRESS_1}
...      client_logical_address= ${TB_LOGICAL_ADDRESS_1}
...      activation_type= ${ACTIVATION_TYPE_1}
Connect UDS Connector      device_name= ${DEVICE_NAME_1}

Open UDS Connection      device_name= ${DEVICE_NAME_1}
Load PDX      ${FILE_1}      ${VARIANT_1}      device_name= ${DEVICE_NAME_1}
${service_name_list_1}=   Create List      readCPUClockFrequencies_Read
Read Data By Name      ${service_name_list_1}      device_name= ${DEVICE_NAME_1}
Close UDS Connection      device_name= ${DEVICE_NAME_1}

Log      Re-opent uds connection device 2
Open UDS Connection      device_name= ${DEVICE_NAME_2}
Read Data By Name      ${service_name_list_2}      device_name= ${DEVICE_NAME_2}

Log      Expected device 2 cannot send readCPUClockFrequencies_Read service like device↵
↵ 1
Run Keyword And Expect Error      ${ERROR_STR}      Read Data By Name      ${↵
↵ service_name_list_1}      device_name= ${DEVICE_NAME_2}
Close UDS Connection      device_name= ${DEVICE_NAME_2}

```

Routine Control By Name

```

Test user can use Routine Control By Name service on ECU
Log      Routine Control By Name service: StartIperfServer_Start

${param_dict}=   Create Dictionary      port=5101      argument=-i 0.5 -B 192.168.1.
${response}=     Routine Control By Name      StartIperfServer_Start      ${param_dict}

Log      ${response}      console=True
FOR      ${item}      IN      @${response.keys()}
Log      ${item} : ${response["${item}"]}      console=True
END

Test user can use Routine Control By Name service if service have sub-service on ECU
Log      Routine Control By Name service: Routine_Control_Start, sub-service: ↵
↵ StartIperfServer_Start

${param_dict}=   Create Dictionary      port=5101      argument=-i 0.5 -B 192.168.1.
${response}=     Routine Control By Name      Routine_Control_Start      ${param_dict}      ↵
↵ sub_service=StartIperfServer

Log      ${response}      console=True
FOR      ${item}      IN      @${response.keys()}
Log      ${item} : ${response["${item}"]}      console=True
END

```

Input Output Control By Name

```

Test user can use Input Output Control By Name service on ECU
Log      Input Output Control By Name service: CAM1PowerSupply_Set

${param_dict}=   Create Dictionary      mode=passiv
${response}=     Input Output Control By Name      CAM1PowerSupply_Set      ${param_dict}

```

```

Log    ${response}    console=True
FOR    ${item}      IN    @${response.keys()}
    Log    ${item} : ${response["${item}"]}    console=True
END

```

Test user can use Input Output Control By Name service if the service has sub-service on ECU ←

```

Log    Input Output Control By Name service: IOControl_Control, sub_service: ←
↳ internalFan_PWM
${param_dict}=    Create Dictionary    pwm=10
${response}=    Input Output Control By Name    IOControl_Control    ${param_dict} ←
↳ sub_service=internalFan_PWM

```

```

Log    ${response}    console=True
FOR    ${item}      IN    @${response.keys()}
    Log    ${item} : ${response["${item}"]}    console=True
END

```

Read Data By Name

Test user can use Read Data By Name service on ECU

```
Log    Use Read Data By Name service
```

```
Log    Use Read Data By Identifier - 25392
```

```

${list_identifiers}=    Create List    0x6330
${res}=    Read Data By Identifier    ${list_identifiers}
Log    ${res}    console=True
Log    ${res[0x6330]}    console=True

```

```
Log    readCPUClockFrequencies_Read
```

```

${service_name_list}=    Create List    readCPUClockFrequencies_Read
${responses}=    Read Data By Name    ${service_name_list}
Log    ${responses}    console=True

```

```

FOR    ${request_id}    IN    @${responses.keys()}
    Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
    ${response}=    Set Variable    ${responses["${request_id}"]}
    FOR    ${item}      IN    @${response.keys()}
        Log    ${item} : ${response["${item}"]}    console=True
    END
END

```

Test Read List Services

```

${list_read_services}=    Create List    TestManager_SWVersion_Read
...                        CTSSWVersion_Read
...                        CPULoad_Read

```

```

FOR    ${service_name}    IN    @${list_read_services}
    Log    Read Data of ${service_name}    console=True
    ${list_service}=    Create List    ${service_name}
    ${res}=    Read Data By Name    ${list_service}
    Log    ${res}    console=True
END

```

Test user can use Read Data By Name service if the services have sub-service on ECU

```

${list_read}=    Create List    Identification_Read
${sub_service}=    Create List    CTSSWVersion
${dict_sub_service}=    Create Dictionary    Identification_Read=${sub_service}

${responses}=    Read Data By Name    ${list_read}    parameters=${dict_sub_service}

```

```
Log    ${responses}    console=True
```

```

FOR    ${request_id}    IN    @${responses.keys()}
    Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
    ${response}=    Set Variable    ${responses["${request_id}"]}

```

```

FOR    ${item}    IN    @{{response.keys()}}
    Log    ${item} : ${response["${item}"]}    console=True
END
END

Append To List    ${list_read}    readCPUClockFrequency_Read    ←
↔ Temperature_Sensor_17_Read

${responses}=    Read Data By Name    ${list_read}    parameters=${dict_sub_service}

Log    ${responses}    console=True

FOR    ${request_id}    IN    @{{responses.keys()}}
    Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
    ${response}=    Set Variable    ${responses["${request_id}"]}
    FOR    ${item}    IN    @{{response.keys()}}
        Log    ${item} : ${response["${item}"]}    console=True
    END
END

${read}=    Create List    readCPUClockFrequency_Read    Identification_Read
${s_service}=    Create List    CTSSWVersion
${dict_sub_service}=    Create Dictionary    Identification_Read=${s_service}
${responses}=    Read Data By Name    ${read}    parameters=${dict_sub_service}

Log    ${responses}    console=True

FOR    ${request_id}    IN    @{{responses.keys()}}
    Log    Key: ${request_id}, Value: ${responses["${request_id}"]}    console=True
    ${response}=    Set Variable    ${responses["${request_id}"]}
    FOR    ${item}    IN    @{{response.keys()}}
        Log    ${item} : ${response["${item}"]}    console=True
    END
END
END

```

Write Data By Name

```

Test user can use Write Data By Name service on ECU
Log    Write Data By Name service

Log    RealTimeClock_Write
${PARAM_DICT}=    Create Dictionary    Day=26    Month=September    Year=2024    Hour↔
↔ =10    Second=45    Minute=0
${res}=    Write Data By Name    RealTimeClock_Write    ${PARAM_DICT}
Log    ${res}    console=True

${DICT}=    Create Dictionary    ipAddress=155
${res}=    Write Data By Name    CTS_IPAddress_Write    ${DICT}
Log    ${res}    console=True

Log    Using service did instead service's name
${res}=    Write Data By Identifier    25382    ${PARAM_DICT}
Log    ${res}    console=True

```

Get Encoded Request Message

```

Test Get Encoded Request Message - Simple request parameters
Log    Test Get Encoded Request Message - mainCPUSTressTest_Start
${service_name}=    Set Variable    mainCPUSTressTest_Start
${param_dict}=    Create Dictionary    cores=5    load=50
${res}=    Get Encoded Request Message    ${service_name}    ${param_dict}
Log    ${res}    console=True
Log    ${res.hex()}    console=True

Test Get Encoded Request Message - Complex request parameters
Load PDX    C:/Users/MAR3HC/Desktop/UDS/robotframework-uds/test/pdx/XTS_MPCI_Maas_1↔
↔ .23.45.pdx    XTS_MPCI_Maas

```

```

Log      Test Get Encoded Request Message - CAN_MasterSlaveEnduranceRun_Start
${service_name}=  Set Variable      CAN_MasterSlaveEnduranceRun_Start
${res}=    Get Encoded Request Message  ${service_name}  ${canConfig}
Log      ${res}      console=True
Log      ${res.hex()}  console=True

```

Get Decoded Request Message

```

Test Get Decoded Response Message
Log      Test Get Decoded Response Message
${service_name}=  Set Variable      StartIperfServer_Start
${response_str}=  Set Variable      \x012#\x00\x00\x18\x05H
${response_byte}= Convert To Bytes  ${response_str}
${res}=    Get Decoded Response Message  ${service_name}  ${response_byte}
Log      ${res}      console=True

```

Send UDS Request By Name

```

Test user can send UDS request without needing to specify the command type
Log      Test user can send UDS request without needing to specify the command type

Log      readCPUClockFrequencies_Read
${service_name_list}=  Create List      readCPUClockFrequencies_Read
${responses}=    Send UDS Request By Name  ${service_name_list}
Log      ${responses}  console=True

FOR      ${request_did}  IN      @${responses.keys()}
Log      Key: ${request_did}, Value: ${responses["${request_did}"]}  console=True
${response}=    Set Variable      ${responses["${request_did}"]}
FOR      ${item}  IN      @${response.keys()}
Log      ${item} : ${response["${item}"]}  console=True
END
END

Log      CAM1PowerSupply_Set
${param_dict_input_output_control}=  Create Dictionary  mode=passiv
${response}=    Send UDS Request By Name  CAM1PowerSupply_Set  ${↔}
↔ param_dict_input_output_control}

Log      ${response}  console=True
FOR      ${item}  IN      @${response.keys()}
Log      ${item} : ${response["${item}"]}  console=True
END

Log      RealTimeClock_Write
${param_dict_write_data_by_name}=  Create Dictionary  Day=26  Month=September  ↔
↔ Year=2024  Hour=10  Second=45  Minute=0
${res}=    Send UDS Request By Name  RealTimeClock_Write  ${↔}
↔ param_dict_write_data_by_name}
Log      ${res}  console=True

Log      Routine Control By Name service: StartIperfServer_Start

${param_dict_routine_control_by_name}=  Create Dictionary  port=5101  argument=↔
↔ -i 0.5 -B 192.168.1.
${response}=    Send UDS Request By Name  StartIperfServer_Start  ${↔}
↔ param_dict_routine_control_by_name}

Log      ${response}  console=True
FOR      ${item}  IN      @${response.keys()}
Log      ${item} : ${response["${item}"]}  console=True
END

```

Chapter 3

DiagnosticServices.py

3.1 robotframework-uds-diagnosticservices-diagnosticservices

3.1.1 robotframework-uds-diagnosticservices-diagnosticservices-convert-sub-param

Recursive convert sub parameters in given request to correct data type

Arguments:

- `odx_param`
/ *Condition*: required / *Type*: object /
The ODX parameters.
- `req_sub_param`
/ *Condition*: required / *Type*: dict /
The dictionary of request parameter.

Returns:

- `req_sub_param`
/ *Type*: dict /
The dictionary of request parameters with the correct data types.

3.1.2 robotframework-uds-diagnosticservices-diagnosticservices-convert-request-data-type

Convert given request parameters (dictionary) to correct data type

Arguments:

- `service`
/ *Condition*: required / *Type*: object /
The diagnostic service.
- `parameter_dict`
/ *Condition*: required / *Type*: dict /
The dictionary of request parameter.

Returns:

- `parameter_dict`
/ *Type*: dict /
The dictionary of request parameters with the correct data types.

3.1.3 robotframework-uds-diagnosticservices-diagnosticservices-get-diag-service-by-name

Retrieve the list of diagnostic services from a PDX file using a specified list of service names.

Arguments:

- `service_name_list`
/ *Condition*: required / *Type*: list /
The list of service names

Returns:

- `diag_service_list`
/ *Type*: list /
The list of diagnostic services from a PDX file.

3.1.4 robotframework-uds-diagnosticservices-diagnosticservices-get-encoded-request-message

Retrieve the encode request message from parameters dictionary.

Arguments:

- `service_name`
/ *Condition*: required / *Type*: str /
The service's names
- `parameter_dict`
/ *Condition*: required / *Type*: dict /
The dictionary of request parameter.

Returns:

- `encode_message`
/ *Type*: bytes /
The encoded message.

3.1.5 robotframework-uds-diagnosticservices-diagnosticservices-get-decode-response-message

Retrieve the encode request message from parameters dictionary.

Arguments:

- `service_name`
/ *Condition*: required / *Type*: str /
The service's names
- `raw_message`
/ *Condition*: required / *Type*: bytes /
The raw message from the response.

Returns:

- `decode_message`
/ *Type*: bytes /
The decoded message.

3.1.6 robotframework-uds-diagnosticservices-diagnosticservices-get-full-positive-response-data

Retrieve the complete byte data from the response, as the UDS removes the service ID.

Arguments:

- `service_name`
/ *Condition*: required / *Type*: str /
The service's names
- `data`
/ *Condition*: required / *Type*: bytes /
The raw message from the response.

Returns:

- `positive_response_data`
/ *Type*: bytes /
The complete byte data from the response.

3.1.7 robotframework-uds-diagnosticservices-diagnosticservices-get-did-codec

Retrieves a dictionary of DID codecs for a given diagnostic service ID.

Arguments:

- `service_id`
/ *Condition*: required / *Type*: int /
The service's did

Returns:

- `did_codec`
/ *Type*: dict /
A dictionary where the keys are DIDs

3.2 robotframework-uds-diagnosticservices-pdxcodec

3.3 robotframework-uds-diagnosticservices-serviceid

Chapter 4

UDSKeywords.py

4.1 robotframework-uds-udskeywords-udsdevicemanager

4.2 robotframework-uds-udskeywords-udsdevice

4.3 robotframework-uds-udskeywords-udskeywords

4.3.1 robotframework-uds-udskeywords-udskeywords-connect-uds-connector

Connects a UDS connector for the specified device.

Arguments:

- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" /
Name of the device to connect to. If the device does not exist, a *ValueError* will be raised.
- `config`
/ *Condition*: optional / *Type*: dict / *Default*: `default_client_config` /
Configuration settings for the UDS client, applied if the device is not already available.
- `close_connection`
/ *Condition*: optional / *Type*: bool / *Default*: False /
Indicates whether to close the connection automatically when done.

Raises:

- `ValueError`
Raised if the specified device does not exist, suggesting the use of "Create UDS Connector" to create a new device.

Returns:

- `None`
No return value. The function initializes or updates the UDS connector for the specified device if not already available.

4.3.2 robotframework-uds-udskeywords-udskeywords-create-uds-connector

Establishes a connection with an ECU.

Arguments:

- `communication_name`
/ *Type*: str / *Condition*: required /
Specifies the type of communication to establish.
- `ecu_ip_address`
/ *Type*: str / *Condition*: required /
The IP address of the ECU for establishing the connection. Should be a valid IPv4 (e.g., "192.168.1.1") or IPv6 address (e.g., "2001:db8::").
- `ecu_logical_address`
/ *Type*: any / *Condition*: required /
The logical address of the ECU.
- `tcp_port`
/ *Type*: int / *Condition*: optional / *Default*: **TCP_DATA_UNSECURED** /
TCP port used for unsecured data communication.
- `udp_port`
/ *Type*: int / *Condition*: optional / *Default*: **UDP_DISCOVERY** /
UDP port used for ECU discovery.
- `activation_type`
/ *Type*: RoutingActivationRequest.ActivationType / *Condition*: optional / *Default*: ActivationTypeDefault /
Specifies the activation type, which can be the default (ActivationTypeDefault) or a value based on application-specific settings.
- `protocol_version`
/ *Type*: int / *Condition*: optional / *Default*: 0x02 /
The version of the protocol used for the connection.
- `client_logical_address`
/ *Type*: int / *Condition*: optional / *Default*: None /
The logical address this DoIP client will use to identify itself. Per specification, this should be within the range 0x0E00 to 0x0FFF.
- `client_ip_address`
/ *Type*: str / *Condition*: optional / *Default*: None /
If specified, binds to this IP as the source for UDP and TCP communication. Can be an IPv4 or IPv6 address, matching the type of `ecu_ip_address`.
- `use_secure`
/ *Type*: Union[bool, ssl.SSLContext] / *Condition*: optional / *Default*: False /
Enables TLS if set to True. Uses a default SSL context by default; can be set to a preconfigured SSL context for more control. If enabled, consider changing `tcp_port` to 3496.
- `auto_reconnect_tcp`
/ *Type*: bool / *Condition*: optional / *Default*: False /
Enables automatic reconnection of TCP sockets if closed by the peer.

4.3.3 robotframework-uds-udskeywords-udskeywords-load-pdx

Load PDX file

Arguments:

- `pdx_file`
/ *Type*: str /
PDX file path
- `variant`
/ *Type*: str /

4.3.4 robotframework-uds-udskeywords-udskeywords-create-config

Creates a configuration for the UDS connector.

Arguments:

- `exception_on_negative_response` : bool
When set to True, raises a `NegativeResponseException` if the server responds with a negative response. If False, the Response's *positive* property will be set to False.
- `exception_on_invalid_response` : bool
When set to True, raises an `InvalidResponseException` if `interpret_response` encounters an invalid response. If False, the Response's *valid* property will be set to False.
- `exception_on_unexpected_response` : bool
When set to True, raises an `UnexpectedResponseException` if the server returns an unexpected response, such as an unmatched subfunction echo. If False, the Response's *unexpected* property will be set to True.
- `security_algo` : Callable[[int, bytes, Any], bytes]
Security algorithm function for the SecurityAccess service.
Signature: `security_algo(level, seed, params) -> bytes`
 - `level` : int — The requested security level.
 - `seed` : bytes — The seed provided by the server.
 - `params` : Any — Parameters provided by `security_algo_params`.
- `security_algo_params` : object or dict
Parameters passed to the security algorithm specified in `security_algo`.
- `data_identifiers` : dict[int, Union[str, DidCodec]]
A dictionary mapping data identifiers to a codec (string or `DidCodec`) for encoding/decoding values in services like `ReadDataByIdentifier`, `WriteDataByIdentifier`, etc.
- `input_output` : dict[int, Union[str, DidCodec, dict]]
Dictionary mapping IO data identifiers to a codec for `InputOutputControlByIdentifier` service. Supports composite codecs with sub-dictionaries specifying bitmasks.
- `tolerate_zero_padding` : bool
When True, ignores trailing zeros in response data to prevent `InvalidResponseException` if the protocol uses zero-padding.
- `ignore_all_zero_dtc` : bool For `ReadDTCInformation` service, skips DTCs with an ID of 0x000000, useful if the protocol uses zero-padding. See online documentation for further details.
- `server_address_format` : int
Specifies the `MemoryLocation` address format to use when not explicitly provided.
- `server_memorysize_format` : int
Specifies the `MemoryLocation` memory size format to use when not explicitly provided.
- `extended_data_size` : dict[int, int]
Specifies DTC extended data record sizes.

Example:

```
{
    0x123456: 45, # DTC 0x123456 has an extended data size of 45 bytes.
    0x123457: 23 # DTC 0x123457 has an extended data size of 23 bytes.
}
```

- `dtc_snapshot_did_size` : int
Number of bytes for encoding data identifiers in `ReadDTCInformation` (default: 2).

- `standard_version` : int
UDS standard version, valid values are 2006, 2013, or 2020 (default: 2020).
- `request_timeout` : float
Maximum wait time (in seconds) for a response after sending a request. Defaults to 5 seconds. Set to None to wait indefinitely.
- `p2_timeout` : float
Maximum wait time (in seconds) for a first response after sending a request, per ISO 14229-2:2013 (default: 1 second).
- `p2_star_timeout` : float
Maximum wait time (in seconds) after receiving a requestCorrectlyReceived-ResponsePending (0x78) response from the server (default: 5 seconds).
- `use_server_timing` : bool
When True, uses P2 and P2* timing values provided by the server for sessions with 2013 or later standards. Defaults to True.

4.3.5 robotframework-uds-udskeywords-udskeywords-get-uds-device-config-by-keys

Retrieves the UDS device configuration for the specified keys.

Arguments:

- `keys`
/ *Condition*: optional / *Type*: list / A list of configuration keys to retrieve from the UDS device. If no keys are provided, the full configuration will be returned.
- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" / The name of the device for which the configuration should be retrieved.

Returns:

- `configs`
/ *Type*: dict / A dictionary containing the configuration values for the specified keys.

4.3.6 robotframework-uds-udskeywords-udskeywords-update-uds-device-config-by-keys

Updates the UDS device configuration by multiple keys.

Arguments:

- `keys_dict`
/ *Condition*: required / *Type*: dict / A dictionary where keys are configuration keys and values are the new values to set for those keys.
- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" / The name of the device for which the configuration should be updated. If the device does not exist, a *ValueError* will be raised.

Returns:

- No return value. The method updates the configuration of the specified UDS device with the provided key-value pairs.

4.3.7 robotframework-uds-udskeywords-udskeywords-set-config

This method sets the UDS config.

Arguments:

- `config`
/ *Type*: Configuration /
The configuration to set for the UDS client.
- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" / The name of the device for which the configuration should be set. If the device does not exist, a *ValueError* will be raised.

Returns:

- No return value. The method updates the configuration of the specified UDS device with the provided configuration.

4.3.8 robotframework-uds-udskeywords-udskeywords-connect

Opens a UDS connection.

Arguments:

- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" / The name of the device for which the configuration should be set. If the device does not exist, a *ValueError* will be raised.

Returns:

- No return value. The method opens the UDS connection for the specified device.

4.3.9 robotframework-uds-udskeywords-udskeywords-disconnect

Closes a UDS connection.

Arguments:

- No specific arguments for this method.

4.3.10 robotframework-uds-udskeywords-udskeywords-access-timing-parameter

Sends a generic request for AccessTimingParameter service.

Arguments:

- `access_type`
/ *Condition*: required / *Type*: int /
The service subfunction:
 - `readExtendedTimingParameterSet` = 1
 - `setTimingParametersToDefaultValues` = 2
 - `readCurrentlyActiveTimingParameters` = 3
 - `setTimingParametersToGivenValues` = 4
- `timing_param_record`
/ *Condition*: optional / *Type*: bytes /
The parameters data. Specific to each ECU.

Returns:

- `response`
/ *Type*: Response /
The response from the AccessTimingParameter service request.

4.3.11 robotframework-uds-udskeywords-udskeywords-clear-diagnostic-information

Requests the server to clear its active Diagnostic Trouble Codes.

Arguments:

- `group`
/ *Type*: int /
The group of DTCs to clear. It may refer to Powertrain DTCs, Chassis DTCs, etc. Values are defined by the ECU manufacturer except for two specific values:
 - 0x000000 : Emissions-related systems
 - 0xFFFFFFFF : All DTCs
- `memory_selection`
/ *Condition*: optional / *Type*: int /
MemorySelection byte (0-0xFF). This value is user-defined and introduced in the 2020 version of ISO-14229-1. Only added to the request payload when different from None. Default: None.

Returns:

- `response`
/ *Type*: Response /
The response from the server after attempting to clear the active Diagnostic Trouble Codes.

4.3.12 robotframework-uds-udskeywords-udskeywords-communication-control

Switches the transmission or reception of certain messages on/off with CommunicationControl service.

Arguments:

- `control_type`
/ *Condition*: required / *Type*: int /
The action to request such as enabling or disabling some messages. This value can also be ECU manufacturer-specific:
 - enableRxAndTx = 0
 - enableRxAndDisableTx = 1
 - disableRxAndEnableTx = 2
 - disableRxAndTx = 3
 - enableRxAndDisableTxWithEnhancedAddressInformation = 4
 - enableRxAndTxWithEnhancedAddressInformation = 5
- `communication_type`
/ *Condition*: required / *Type*: CommunicationType<CommunicationType>, bytes, int /
Indicates what section of the network and the type of message that should be affected by the command. Refer to CommunicationType<CommunicationType> for more details. If an *integer* or *bytes* is given, the value will be decoded to create the required CommunicationType<CommunicationType> object.

- `node_id`

/ *Condition*: optional / *Type*: int /

DTC memory identifier (`nodeIdentificationNumber`). This value is user-defined and introduced in the 2013 version of ISO-14229-1. Possible only when control type is `enableRxAndDisableTxWithEnhancedAddressInformation` or `enableRxAndTxWithEnhancedAddressInformation`. Only added to the request payload when different from `None`. Default: `None`.

Returns:

- `response`

/ *Type*: Response /

The response from the `CommunicationControl` service request.

4.3.13 robotframework-uds-udskeywords-udskeywords-control-dtc-setting

Controls some settings related to the Diagnostic Trouble Codes by sending a `ControlDTCSetting` service request. It can enable/disable some DTCs or perform some ECU-specific configuration.

Arguments:

- `setting_type`

/ *Condition*: required / *Type*: int /

Allowed values are from 0 to 0x7F:

- `on` = 1
- `off` = 2
- `vehicleManufacturerSpecific` = (0x40, 0x5F) # For logging purposes only.
- `systemSupplierSpecific` = (0x60, 0x7E) # For logging purposes only.

- `data`

/ *Condition*: optional / *Type*: bytes /

Optional additional data sent with the request called *DTCSettingControlOptionRecord*.

Returns:

- `response`

/ *Type*: Response /

The response from the `ControlDTCSetting` service request.

4.3.14 robotframework-uds-udskeywords-udskeywords-diagnostic-session-control

Requests the server to change the diagnostic session with a `DiagnosticSessionControl` service request.

Arguments:

- `newsession`

/ *Condition*: required / *Type*: int /

The session to try to switch:

- `defaultSession` = 1
- `programmingSession` = 2
- `extendedDiagnosticSession` = 3
- `safetySystemDiagnosticSession` = 4

Returns:

- `response`

/ *Type*: Response /

The response from the `DiagnosticSessionControl` service request.

4.3.15 robotframework-uds-udskeywords-udskeywords-dynamically-define-did

Defines a dynamically defined DID.

Arguments:

- did
/ *Type*: int /
The data identifier to define.
- did_definition
/ *Type*: DynamicDidDefinition<DynamicDidDefinition> or MemoryLocation<MemoryLocation> /
The definition of the DID. Can be defined by source DID or memory address. If a MemoryLocation<MemoryLocation> object is given, the definition will automatically be by memory address.

Returns:

- response
/ *Type*: Response /
The response from the request to define the dynamically defined DID.

4.3.16 robotframework-uds-udskeywords-udskeywords-ecu-reset

Requests the server to execute a reset sequence through the ECUReset service.

Arguments:

- reset_type
/ *Condition*: required / *Type*: int /
The type of reset to perform:
 - hardReset = 1
 - keyOffOnReset = 2
 - softReset = 3
 - enableRapidPowerShutDown = 4
 - disableRapidPowerShutDown = 5

Returns:

- response
/ *Type*: Response /
The response from the ECUReset service request.

4.3.17 robotframework-uds-udskeywords-udskeywords-io-control

Substitutes the value of an input signal or overrides the state of an output by sending an InputOutputControlByIdentifier service request.

Arguments:

- did
/ *Condition*: required / *Type*: int /
Data identifier to represent the IO.
- control_param
/ *Condition*: optional / *Type*: int /
Control parameters:

- returnControlToECU = 0
- resetToDefault = 1
- freezeCurrentState = 2
- shortTermAdjustment = 3

- values

Condition: optional / *Type:* list, dict, IOValues<IOValues> /

Optional values to send to the server. This parameter will be given to `DidCodec<DidCodec>.encode()` method. It can be:

- A list for positional arguments
- A dict for named arguments
- An instance of IOValues<IOValues> for mixed arguments

- masks

Condition: optional / *Type:* list, dict, IOMask<IOMask>, bool /

Optional mask record for composite values. The mask definition must be included in `config['input_output']`. It can be:

- A list naming the bit mask to set
- A dict with the mask name as a key and a boolean setting or clearing the mask as the value
- An instance of IOMask<IOMask>
- A boolean value to set all masks to the same value.

Returns:

- response

Type: dict /

The decoded response data.

4.3.18 robotframework-uds-udskeywords-udskeywords-link-control

Controls the communication baudrate by sending a LinkControl service request.

Arguments:

- control_type

Condition: required / *Type:* int /

Allowed values are from 0 to 0xFF:

- verifyBaudrateTransitionWithFixedBaudrate = 1
- verifyBaudrateTransitionWithSpecificBaudrate = 2
- transitionBaudrate = 3

- baudrate

Condition: required / *Type:* Baudrate<Baudrate> /

Required baudrate value when `control_type` is either `verifyBaudrateTransitionWithFixedBaudrate` (1) or `verifyBaudrateTransitionWithSpecificBaudrate` (2).

Returns:

- response

Type: Response /

The response from the LinkControl service request.

4.3.19 robotframework-uds-udskeywords-udskeywords-read-data-by-identifier

Requests a value associated with a data identifier (DID) through the ReadDataByIdentifier service.

Arguments:

- `data_id_list`
/ *Type*: int | list[int] /
The list of DIDs to be read.

Returns:

- `response`
/ *Type*: Response /
The response from the ReadDataByIdentifier service request.

4.3.20 robotframework-uds-udskeywords-udskeywords-read-dtc-information

Performs a ReadDiagnosticInformation service request.

Arguments:

- `subfunction`
/ *Condition*: required / *Type*: int /
The subfunction for the ReadDiagnosticInformation service.
- `status_mask`
/ *Condition*: optional / *Type*: int /
Status mask to filter the diagnostic information.
- `severity_mask`
/ *Condition*: optional / *Type*: int /
Severity mask to filter the diagnostic information.
- `dtc`
/ *Condition*: optional / *Type*: int | Dtc /
The Diagnostic Trouble Code to query. Can be an integer or a Dtc object.
- `snapshot_record_number`
/ *Condition*: optional / *Type*: int /
Snapshot record number to specify the snapshot to read.
- `extended_data_record_number`
/ *Condition*: optional / *Type*: int /
Extended data record number to specify the extended data to read.
- `extended_data_size`
/ *Condition*: optional / *Type*: int /
Size of the extended data to read.
- `memory_selection`
/ *Condition*: optional / *Type*: int /
Memory selection to specify the memory to be accessed.

Returns:

- `response`
/ *Type*: Response /
The response from the ReadDiagnosticInformation service request.

4.3.21 robotframework-uds-udskeywords-udskeywords-read-memory-by-address

Reads a block of memory from the server by sending a ReadMemoryByAddress service request.

Arguments:

- `memory_location`
/ *Condition*: required / *Type*: MemoryLocation<MemoryLocation> /
The address and the size of the memory block to read.

Returns:

- `response`
/ *Type*: Response /
The response from the ReadMemoryByAddress service request.

4.3.22 robotframework-uds-udskeywords-udskeywords-request-download

Informs the server that the client wants to initiate a download from the client to the server by sending a RequestDownload service request.

Arguments:

- `memory_location`
/ *Condition*: required / *Type*: MemoryLocation<MemoryLocation> /
The address and size of the memory block to be written.
- `dfi`
/ *Condition*: optional / *Type*: DataFormatIdentifier<DataFormatIdentifier> /
Optional defining the compression and encryption scheme of the data. If not specified, the default value of 00 will be used, specifying no encryption and no compression.

Returns:

- `response`
/ *Type*: Response /
The response from the RequestDownload service request.

4.3.23 robotframework-uds-udskeywords-udskeywords-request-transfer-exit

Informs the server that the client wants to stop the data transfer by sending a RequestTransferExit service request.

Arguments:

- `data`
/ *Condition*: optional / *Type*: bytes /
Optional additional data to send to the server.

Returns:

- `response`
/ *Type*: Response /
The response from the RequestTransferExit service request.

4.3.24 robotframework-uds-udskeywords-udskeywords-request-upload

Informs the server that the client wants to initiate an upload from the server to the client by sending a RequestUpload service request.

Arguments:

- `memory_location`
/ *Condition*: required / *Type*: `MemoryLocation<MemoryLocation>` /
The address and size of the memory block to be written.
- `dfi`
/ *Condition*: optional / *Type*: `DataFormatIdentifier<DataFormatIdentifier>` /
Optional defining the compression and encryption scheme of the data. If not specified, the default value of 00 will be used, specifying no encryption and no compression.

Returns:

- `response`
/ *Type*: `Response` /
The response from the RequestUpload service request.

4.3.25 robotframework-uds-udskeywords-udskeywords-routine-control

Sends a generic request for the RoutineControl service.

Arguments:

- `routine_id`
/ *Condition*: required / *Type*: `int` /
The 16-bit numerical ID of the routine.
- `control_type`
/ *Condition*: required / *Type*: `int` /
The service subfunction. Valid values are:
 - `startRoutine = 1`
 - `stopRoutine = 2`
 - `requestRoutineResults = 3`
- `data`
/ *Condition*: optional / *Type*: `bytes` /
Optional additional data to give to the server.

Returns:

- `response`
/ *Type*: `Response` /
The response from the RoutineControl service request.

4.3.26 robotframework-uds-udskeywords-udskeywords-security-access

Successively calls `request_seed` and `send_key` to unlock a security level with the SecurityAccess service. The key computation is done by calling `config['security_algo']`.

Arguments:

- `level`
/ *Condition*: required / *Type*: int /
The level to unlock. Can be the odd or even variant of it.
- `seed_params`
/ *Condition*: optional / *Type*: bytes /
Optional data to attach to the RequestSeed request (securityAccessDataRecord).

Returns:

- `response`
/ *Type*: Response /
The response from the SecurityAccess service request.

4.3.27 robotframework-uds-udskeywords-udskeywords-tester-present

Sends a TesterPresent request to keep the session active.

Arguments:

- No specific arguments for this method.

Returns:

- `response`
/ *Type*: Response /
The response from the TesterPresent request.

4.3.28 robotframework-uds-udskeywords-udskeywords-transfer-data

Transfers a block of data to/from the client to/from the server by sending a TransferData service request and returning the server response.

Arguments:

- `sequence_number`
/ *Condition*: required / *Type*: int /
Corresponds to an 8-bit counter that should increment for each new block transferred. Allowed values are from 0 to 0xFF.
- `data`
/ *Condition*: optional / *Type*: bytes /
Optional additional data to send to the server.

Returns:

- `response`
/ *Type*: Response /
The response from the TransferData service request.

4.3.29 robotframework-uds-udskeywords-udskeywords-write-data-by-identifier

Requests to write a value associated with a data identifier (DID) through the WriteDataByIdentifier service.

Arguments:

- `did`
/ *Condition*: required / *Type*: int /
The DID to write its value.
- `value`
/ *Condition*: required / *Type*: dict /
Value given to the `DidCodec.encode` method. The payload returned by the codec will be sent to the server.

Returns:

- `response`
/ *Type*: Response /
The response from the `WriteDataByIdentifier` service request.

4.3.30 robotframework-uds-udskeywords-udskeywords-write-memory-by-address

Writes a block of memory in the server by sending a `WriteMemoryByAddress` service request.

Arguments:

- `memory_location`
/ *Condition*: required / *Type*: MemoryLocation<MemoryLocation> /
The address and the size of the memory block to write.
- `data`
/ *Condition*: required / *Type*: bytes /
The data to write into memory.

Returns:

- `response`
/ *Type*: Response /
The response from the `WriteMemoryByAddress` service request.

4.3.31 robotframework-uds-udskeywords-udskeywords-request-file-transfer

Sends a `RequestFileTransfer` request **Arguments:**

- `moop`
/ *Condition*: required / *Type*: int /
Mode of operation:
 - AddFile = 1
 - DeleteFile = 2
 - ReplaceFile = 3
 - ReadFile = 4
 - ReadDir = 5
 - ResumeFile = 6
- `path`
/ *Condition*: required / *Type*: str /
The path of the file or directory.
- `dfi`
/ *Condition*: optional / *Type*: DataFormatIdentifier /
DataFormatIdentifier defining the compression and encryption scheme of the data. Defaults to no compression and no encryption. Use for:

- AddFile = 1
- ReplaceFile = 3
- ReadFile = 4
- ResumeFile = 6

- filesize

/ *Condition*: optional / *Type*: int | Filesize /

The filesize of the file to write. If *Filesize*, uncompressed and compressed sizes will be encoded as needed. Use for:

- AddFile = 1
- ReplaceFile = 3
- ResumeFile = 6

Returns:

- response

/ *Type*: Response /

The response from the file operation.

4.3.32 robotframework-uds-udskeywords-udskeywords-authentication

Sends an Authentication request introduced in 2020 version of ISO-14229-1. **Arguments:**

- authentication_task

/ *Condition*: required / *Type*: int /

The authentication task (subfunction) to use:

- deAuthenticate = 0
- verifyCertificateUnidirectional = 1
- verifyCertificateBidirectional = 2
- proofOfOwnership = 3
- transmitCertificate = 4
- requestChallengeForAuthentication = 5
- verifyProofOfOwnershipUnidirectional = 6
- verifyProofOfOwnershipBidirectional = 7
- authenticationConfiguration = 8

- communication_configuration

/ *Condition*: optional / *Type*: int /

Configuration about security in future diagnostic communication (vehicle manufacturer specific). Allowed values are from 0 to 255.

- certificate_client

/ *Condition*: optional / *Type*: bytes /

The certificate to verify.

- challenge_client

/ *Condition*: optional / *Type*: bytes /

Client challenge containing vehicle manufacturer-specific data or a random number.

- algorithm_indicator

/ *Condition*: optional / *Type*: bytes /

Algorithm used in Proof of Ownership (POWN). This is a 16-byte value containing the BER-encoded OID of the algorithm.

- `certificate_evaluation_id`
/ *Condition*: optional / *Type*: int /
Unique ID for evaluating the transmitted certificate. Allowed values are from 0 to 0xFFFF.
- `certificate_data`
/ *Condition*: optional / *Type*: bytes /
Certificate data for verification.
- `proof_of_ownership_client`
/ *Condition*: optional / *Type*: bytes /
Proof of Ownership of the challenge to be verified by the server.
- `ephemeral_public_key_client`
/ *Condition*: optional / *Type*: bytes /
Client's ephemeral public key for Diffie-Hellman key agreement.
- `additional_parameter`
/ *Condition*: optional / *Type*: bytes /
Additional parameter provided if required by the server.

Returns:

- `response`
/ *Type*: Response /
The server's response to the authentication request.

4.3.33 robotframework-uds-udskeywords-udskeywords-routine-control-by-name

Sends a request for the RoutineControl service by routine name.

Arguments:

- param `routine_name` (required): Name of the routine
– type `routine_name`: str
- param `data` (optional): Optional additional data to give to the server
– type `data`: bytes

Returns:

- `response`
/ *Type*: Response /
The server's response to the RoutineControl request.

4.3.34 robotframework-uds-udskeywords-udskeywords-read-data-by-name

Get diagnostic service list by a list of service names.

Arguments:

- param `service_name_list`: List of service names * type `service_name_list`: list[str]
- param `parameters`: Parameter list * type `parameters`: list[]

Returns:

- `response` / *Type*: Response / The server's response containing the diagnostic service list.

4.3.35 robotframework-uds-udskeywords-udskeywords-get-encoded-request-message

Get diagnostic service encoded request (bytes value).

Arguments:

- param `service_name`: Diagnostic service's name * type `service_name`: string
- param `parameters_dict`: Parameter dictionary * type `parameters_dict`: dict

Returns:

- `encoded_message` / *Type*: bytes / The encoded message in bytes value.

4.3.36 robotframework-uds-udskeywords-udskeywords-get-decoded-positive-response-message

Get diagnostic service decoded positive response message.

Arguments:

- param `service_name`: Diagnostic service's name * type `service_name`: string
- param `response_data`: Bytes data from the response * type `parameters_dict`: bytes
- param `device_name`: Name of the device * type `device_name`: string

Returns:

- `decode_message` / *Type*: dict / The decode message in dictionary.

4.3.37 robotframework-uds-udskeywords-udskeywords-write-data-by-name

Requests to write a value associated with a name of service through the WriteDataByName service.

Arguments:

- `service_name`
/ *Condition*: required / *Type*: str /
The name to write its value.
- `value`
/ *Condition*: required / *Type*: dict /
Value given to the `DidCodec.encode` method. The payload returned by the codec will be sent to the server.
- `sub_services` / *Condition*: optional / *Type*: str /
A dictionary representing the sub-services of the main service, formatted as: { 'Name of main service': ['Name of sub-service'] }

Returns:

- `response`
/ *Type*: Response /
The response from the `WriteDataByIdentifier` service request.

4.3.38 robotframework-uds-udskeywords-udskeywords-io-control-by-name

Sends a request for the IOControl service by name of input output control service.

Arguments:

- `io_control_name`
/ *Condition*: required / *Type*: str /
Name of the input output control service
- `value`
/ *Condition*: optional / *Type*: dict /
Optional additional data to give to the server
- `masks`
/ *Condition*: optional / *Type*: list, dict, IOMask<IOMask>, bool /
Optional mask record for composite values. The mask definition must be included in `config['input_output']`. It can be:
 - A list naming the bit mask to set
 - A dict with the mask name as a key and a boolean setting or clearing the mask as the value
 - An instance of IOMask<IOMask>
 - A boolean value to set all masks to the same value.

Returns:

- `response`
/ *Type*: dict /
The decoded response data.

4.3.39 robotframework-uds-udskeywords-udskeywords-send-uds-request-by-name

Sends a UDS request by the name of the specified diagnostic service.

Arguments:

- `service_name`
/ *Condition*: optional / *Type*: str / *Default*: None /
Name of the diagnostic service to request.
- `device_name`
/ *Condition*: optional / *Type*: str / *Default*: "default" /
Name of the device to which the UDS request will be sent.
- `kwargs`
/ *Condition*: optional / *Type*: dict /
Additional parameters specific to certain services. Possible values include:
 - `reset_type`: (int) Reset type for ECU reset services.
 - `parameters`: (dict) Parameters for WRITE_DATA_BY_IDENTIFIER, INPUT_OUTPUT_CONTROL_BY_IDENTIFIER and ROUTINE_CONTROL services.
 - `mask`: (any) Mask value for the INPUT_OUTPUT_CONTROL_BY_IDENTIFIER service.
 - `groups`: (int) Group identifiers for the CLEAR_DIAGNOSTIC_INFORMATION service (default: 0xFFFFFFFF).
 - `memory_selection`: (any) Memory selection for the CLEAR_DIAGNOSTIC_INFORMATION service.
 - `control_type`: (int) Control type for COMMUNICATION_CONTROL service.
 - `communication_type`: (int) Communication type for COMMUNICATION_CONTROL service.

- node_id: (any) Node ID for COMMUNICATION_CONTROL service.
- setting_type: (int) Setting type for CONTROL_DTC_SETTING service.
- data: (any) Data for CONTROL_DTC_SETTING and TRANSFER_EXIT services.
- session_type: (int) Session type for DIAGNOSTIC_SESSION_CONTROL service.
- subfunction: (int) Subfunction for READ_DTC_INFORMATION service.
- status_mask: (any) Status mask for READ_DTC_INFORMATION service.
- severity_mask: (any) Severity mask for READ_DTC_INFORMATION service.
- dtc: (any) Diagnostic Trouble Code (DTC) for READ_DTC_INFORMATION service.
- snapshot_record_number: (any) Snapshot record number for READ_DTC_INFORMATION service.
- extended_data_record_number: (any) Extended data record number for READ_DTC_INFORMATION service.
- extended_data_size: (any) Extended data size for READ_DTC_INFORMATION service.
- memory_location: (any) Memory location for READ_MEMORY_BY_ADDRESS, REQUEST_DOWNLOAD, REQUEST_UPLOAD, and WRITE_MEMORY_BY_ADDRESS services.
- dfi: (any) Data Format Identifier (DFI) for REQUEST_DOWNLOAD and REQUEST_UPLOAD services.
- level: (any) Security level for SECURITY_ACCESS service.
- seed_params: (any) Seed parameters for SECURITY_ACCESS service.
- sequence_number: (int) Sequence number for TRANSFER_DATA service.
- data: (any) Data for TRANSFER_DATA and TRANSFER_EXIT services.

Returns:

- response

/ *Type*: Response /

The decoded response data from the service request.

4.3.40 robotframework-uds-udskeywords-udskeywords-reconnect

Attempts to re-establish the connection.

Arguments:

- close_delay

/ *Condition*: optional / *Type*: float / *Default*: 2 second /

Time to wait between closing and re-opening socket

- device_name

/ *Condition*: optional / *Type*: str / *Default*: "default" /

Name of the device to which the UDS request will be sent.

Chapter 5

`__init__.py`

RobotFramework_UDS is a Robot Framework library aimed to provide UDP client to handle request/response.

Chapter 6

Appendix

About RobotFramework-UDS:

Author

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Version

0.2.0 (23.02.2026)

Short Description

Robot Framework keywords for UDS (Unified Diagnostic Services) communication

Homepage

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Documentation

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Sources

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Issues

[Issues](#)

Python required

≥ 3.11

License

Apache-2.0

Chapter 7

History

0.1.0	09/2024
<i>Initial version</i>	
0.1.4	09/2024
<i>- Update Write Data By Name keyword to return response with given service name instead of did.</i>	
0.1.5	10/2024
<i>- Update Read Data By Name keyword to return response with given service name instead of did.</i>	
<i>- Update Get Encoded Request Message keyword to support convert string to proper data type for request parameters.</i>	
<i>- Update Get Decoded Response Message keyword to support decoded response data.</i>	
0.1.6	10/2024
<i>Temporary solution for encoding byte field param with dynamic length</i>	
0.1.7	10/2024
<i>Improve the encoding function for byte data</i>	
0.1.8	10/2024
<i>- Remove temporary solution for encoding byte field param with dynamic length</i>	
<i>- Update package requirements to use <code>odxtools</code> version greater than 8.2.1</i>	
0.1.9	10/2024
<i>Add Input Output Control By Name keyword</i>	
0.1.10	10/2024
<i>Add Send UDS Request By Name keyword</i>	
0.1.11	02/2025
<i>Fix the type error that occurs when user utilize string parameters in the Create UDS Connector keyword</i>	
0.1.12	02/2025
<i>Update Read/Write data by identifier keywords can be used without the need for PDX file</i>	
0.1.13	03/2025
<i>Support new pdx format using TABLE-KEY</i>	
0.1.14	03/2025

<i>Add the Reconnect keyword to enable users to attempt re-establishing the connection</i>	
0.1.15	05/2025
<i>Align Read data by name keyword's response to contain short name of service</i>	
0.1.16	08/2025
<i>Added keywords for managing UDS device configurations:</i> <i>- Get UDS Device Config By Keys</i> <i>- Update UDS Device Config By Keys</i>	
0.2.0	23.02.2026
<i>Usage of Setuptools replaced by usage of PIP/TOML/Setuptools</i>	

RobotFramework_UDS.pdf

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