

# RobotFramework\_DoIP

**v. 0.2.0**

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# Chapter 1

## Introduction

### 1.1 Overview

**robotframework-doip** is a Robot Framework library specifically designed for interacting with Electronic Control Units (ECUs) using the Diagnostics over Internet Protocol (DoIP).

At its core, DoIP serves as a communication bridge between external diagnostic tools and a vehicle's ECUs. This library, RobotFrameworkDoIP, provides a set of keywords that enable users to perform diagnostic operations and engage with ECUs, facilitating automated testing processes and interaction with vehicles through the DoIP protocol.

The **robotframework-doip** sources can be found in repository **robotframework-doip**: [DoIP](#)

### 1.2 Abbreviations

Table 1.1: Abbreviation

Abbreviation / Acronym	Description
ARP	Address Resolution Protocol
DHCP	Diagnostic Host Configuration Protocol
EID	Entity identifier
GID	Group identifier
ICMP	Internet Control Message Protocol
IP	Internet Protocol
IPv4	Internet Protocol version 4
IPv6	Internet Protocol version 6
TCP	Transmission Control Protocol
TCP/IP	A family of communication protocols used in computer networks
VIN	Vehicle Identification Number
UDP	User Datagram Protocol

## 1.3 Terms and definitions

### 1.3.1 Diagnostic Power Mode

The vehicle internal power supply status affects the diagnostic capabilities of all ECUs on the in-vehicle network and identifies the status of all ECUs in all gateway subnetworks that allow diagnostic communication. Its purpose is to provide external test equipment with whether it can be performed on the connected vehicle.

### 1.3.2 Transport protocol

Transport protocols reside on top of the IP protocol. Transport protocols run over the best-effort IP layer to provide a mechanism for applications to communicate with each other without directly interacting with the IP layer.

The important thing here is that DoIP does not represent a diagnostic protocol according to ISO 13400 but rather an expanded transport protocol. This means that the transmission of diagnostic packets is defined in DoIP, but the contained diagnostic services continue to be specified and described by diagnostic protocols such as KWP2000 and UDS.

### 1.3.3 Diagnostics tester

A diagnostic tester / diagnostic client enables the sending of diagnostic requests. Testers can take the form of external devices, such as in repair shops, or on-board testers in the vehicle. The receiving ECU must process the diagnostic requests and return an associated diagnostic response to the tester.

### 1.3.4 Diagnostics gateway

The gateway assumes the role of the intermediary. Requests of the tester are forwarded to internal networks so that a desired ECU can receive and process them. As soon as a response from the requested ECU is available, the gateway routes this back to the tester.

### 1.3.5 Logical addresses

A diagnostic gateway always requires two pieces of information in order to forward diagnostic requests and responses.

- First, it requires a logical address that uniquely identifies the ECU to be diagnosed in the vehicle, equivalent to the ecu logical address parameter.
- Second, the gateway must know which messages on the respective bus system or network will be used to send diagnostic requests and to receive diagnostic responses, equivalent to client logical addressp parameter.

Both pieces of information must be available for an ECU for it to be accessible via the gateway.

# Chapter 2

## Description

### 2.1 System Overview

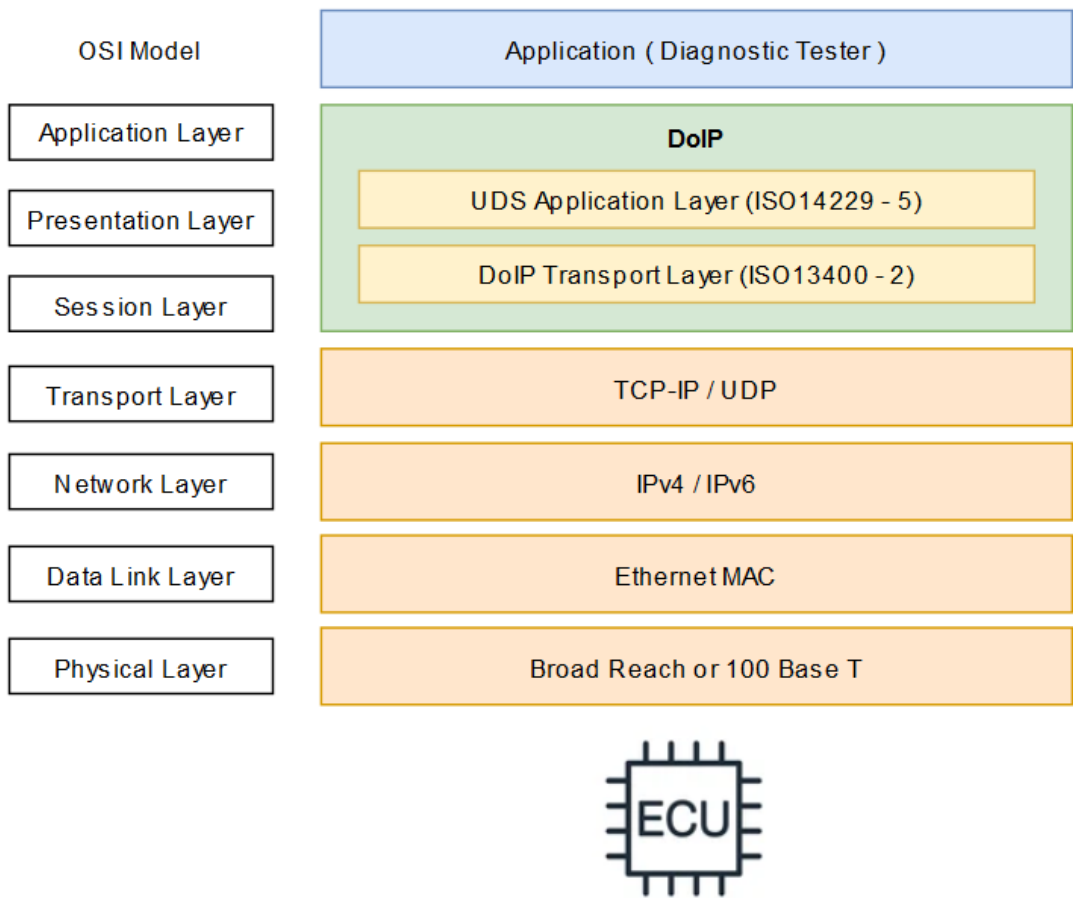


Figure 2.1: System overview

- The DoIP (Diagnostics over Internet Protocol) protocol is a standard for vehicle diagnostics that allows communication between diagnostic tester devices and electronic control units (ECU) over Ethernet networks.
- DoIP is a standardized diagnostic transport protocol according to ISO 13400.
  - DoIP Transport Layer (ISO 13400-2) is equipped with features to establish and maintain connection between external tester device and DoIP gateway inside the vehicle.
  - UDS application layer (ISO 14229-5) is the application profile that implements UDS on IP.
- The overall goal of the protocol is to encapsulate diagnostics messages of protocol standards like Unified Diagnostic Services (UDS) and route them to and from the ECU.

- The DoIP gateway or server can be a part of the ECU. A vehicle can have multiple DoIP entities and multiple testing devices and ECUs can route their traffic via a single DoIP entity.
- DoIP uses both User Datagram Protocol (UDP) and Transmission Control Protocol (TCP) for specific phases of the underlying layer. The initial announcement and identification messages are over UDP, after which the communication switches over to TCP.

## 2.2 Multiple Connections

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

### Example

```
Test user can connect multiple connection
Log    Connect to ECU 1

Connect To ECU      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}

Send Diagnostic Message 1001    device_name= ${DEVICE_NAME_1}
${resp}=    Receive Diagnostic Message    device_name= ${DEVICE_NAME_1}
Log To Console    ${resp}
Disconnect    device_name= ${DEVICE_NAME_1}

Log    Connect to ECU 2
Connect To ECU      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}

Send Diagnostic Message 1001    device_name= ${DEVICE_NAME_2}
${resp}=    Receive Diagnostic Message    device_name= ${DEVICE_NAME_2}
Log To Console    ${resp}
Disconnect    device_name= ${DEVICE_NAME_2}
```

## 2.3 DoIP application scenarios

This section will provide some features along with examples through system above:

- Vehicle identification and announcement: Is necessary to detect who is participating in the DoIP communication.
- Request diagnostic message: Request for diagnostic information, which is crucial for diagnosing vehicle issues and ensuring effective communication within the DoIP network.
- Routing Activation: Allows that single Diagnostic Message pathes are activated or not to treat different protocols different (like UDS and OBD) and to also treat single testers different.
- Entity DoIP (Gateway): Provides general information of the single DoIP entity. Usually used by the testers to get the current DoIP protocol relevant information from the single DoIPEntities.
- Alive mechanism: Is used to maintain different tester connections.

### 2.3.1 Example of Diagnostic Process

#### Vehicle Diagnostics

- **Use Case:**  
A vehicle diagnostic tool needs to establish a DoIP connection to communicate with an Electronic Control Unit

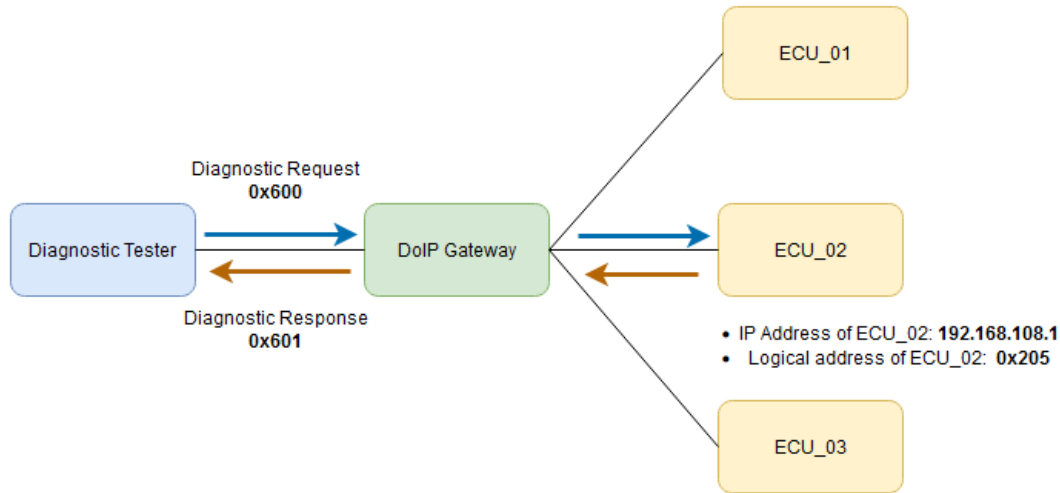


Figure 2.2: Vehicle diagnostic process demonstration

(ECU) within a vehicle for diagnostic purposes.

- **Scenario:**

The diagnostic tool initiates a connection to the ECU's IP address (192.168.108.1) and logical address 517 (0x205) using the **robotframework-doip** library.

It sends a diagnostic message (600) to the ECU, receives a response, logs the response to the console, and then disconnects from the ECU.

```

*** Settings ***
Library      RobotFramework_DoIP

*** Test Cases ***
Test Establish an DoIP connection
    # Establish an connection to ecu ip address and ecu logical address
    Connect To ECU      192.168.108.1      517
    Send Diagnostic Message      600
    ${res}= Receive Diagnostic Message
    Log To Console      ${resp}
    Disconnect
  
```

## Remote Testing

- **Use Case:**

A remote testing environment requires a connection between a target tester and an ECU located in a different location.

- **Scenario:**

The target tester, located at IP address 192.168.108.20, establishes a DoIP connection to the ECU at IP address 192.168.108.1 and logical address 517 (0x205). Additionally, the target tester specifies its own logical address 1895 (0x767) using the **robotframework-doip** library.

It sends a diagnostic message (600) to the ECU, receives a response, logs the response to the console, and then disconnects from the ECU.

```

*** Settings ***
Library      RobotFramework_DoIP

*** Test Cases ***
Test Establish an DoIP connection between specific tester and target ECU
    # Establish an connection to ecu ip address and ecu logical address
    Connect To ECU      192.168.108.1      517      client_ip_address=192.168.108.20  ←
    ↩ client_logical_address=1895
  
```



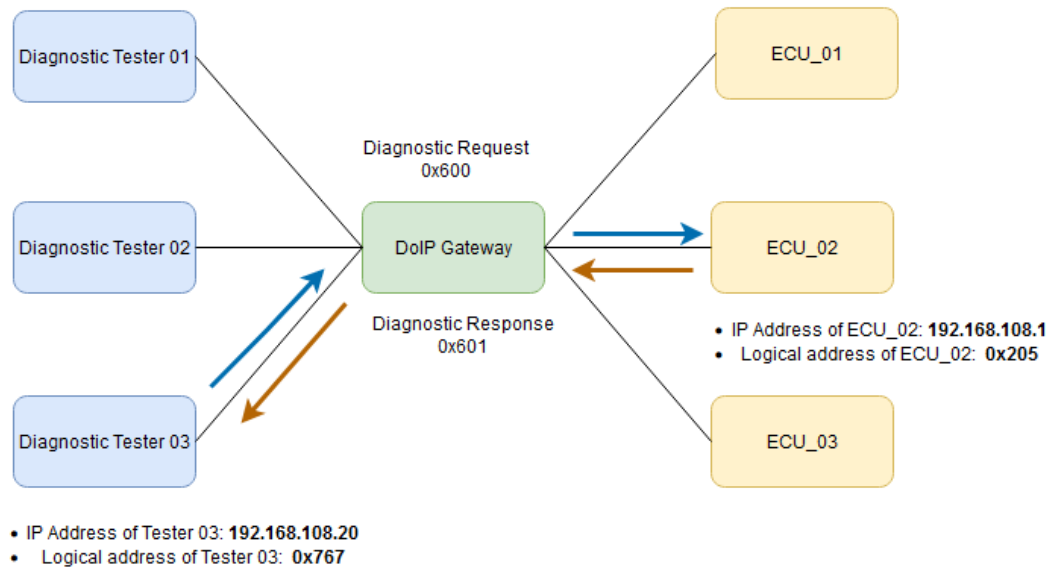


Figure 2.3: Remote diagnostic process demonstration

```

Send Diagnostic Message      600
${res}= Receive Diagnostic Message
Log To Console      ${resp}
Disconnect

```

### 2.3.2 Example of Vehicle Identification

- **Use Case:**  
A diagnostic tool needs to request vehicle identification information from an Electronic Control Unit (ECU) within a vehicle.
- **Scenario:**  
The diagnostic tool initiates a DoIP connection to the ECU's IP address (192.168.108.1) and logical address (205) using the **robotframework-doip** library. It then sends a request for vehicle identification information to the ECU.

```

*** Settings ***
Library      RobotFramework_DoIP

*** Test Cases ***
Test Request Vehicle Identification
    Connect To ECU      192.168.108.1      205
    Request Vehicle Identification

```

## Chapter 3

# The Ecu Simulator

This chapter provides a detailed explanation of the utilization of the ECU simulator through DoIP base on doipclient library. It serves for development or testing scenarios where a physical device is not available.

The ECU simulator is designed to receive messages and respond accordingly to the following types of messages:

- Alive Check Request
- Diagnostic Power Mode Request
- Doip Entity Status Request
- Routing Activation Request
- Vehicle Identification Request

### 3.1 Initialize

This function sets up an instance of an ECU, initializes its attributes with default values, and includes placeholders for various properties that can be customized based on specific requirements.

```
def __init__(self, ecu_type, ip_address, tcp_port, udp_port):
    # Initialize ECU attributes with default values
    self.ecu_type = ecu_type
    self.ip_address = ip_address
    self.tcp_port = tcp_port
    self.udp_port = udp_port
    self.tcp_socket = None
    self.udp_socket = None
    # Set default values for various ECU properties
    # These values might be placeholders and can be updated based on your actual ↔
    ↪ requirements
    self._ecu_logical_address = 3584
    self._client_logical_address = 3584
    self._logical_address = 55
    self._response_code = doip_message.RoutingActivationResponse.ResponseCode.Success
    self._diagnostic_power_mode = doip_message.DiagnosticPowerModeResponse.↔
    ↪ DiagnosticPowerMode.Ready
    self._node_type = 1
    self._max_concurrent_sockets = 16
    self._currently_open_sockets = 1
    self._max_data_size = None
    self._vin = '19676527011956855057'
    self._eid = b'11111'
    self._gid = b'22222'
    self._further_action_required = doip_message.VehicleIdentificationResponse.↔
    ↪ FurtherActionCodes.NoFurtherActionRequired
    self._vin_sync_status = doip_message.VehicleIdentificationResponse.↔
    ↪ SynchronizationStatusCodes.Synchronized
```

## 3.2 Start

This method is responsible for initializing and setting up TCP and UDP sockets, binding them to specific IP addresses and ports, and then starting separate threads to handle the communication on these sockets concurrently.

```
def start(self):
    # Create TCP socket
    self.tcp_socket = socket.socket(socket.AF_INET, socket.SOCK_STREAM)
    self.tcp_socket.bind((self.ip_address, self.tcp_port))
    self.tcp_socket.listen(5)

    # Create UDP socket
    self.udp_socket = socket.socket(socket.AF_INET, socket.SOCK_DGRAM)
    self.udp_socket.bind((self.ip_address, self.udp_port))

    # Start listening on separate threads
    tcp_thread = threading.Thread(target=self.listen_tcp)
    udp_thread = threading.Thread(target=self.listen_udp)

    tcp_thread.start()
    udp_thread.start()
```

### Explanation:

#### 1. TCP Socket Setup

- A TCP socket is created using the socket module with the `socket.AF_INET` family (IPv4) and `socket.SOCK_STREAM` type (TCP).
- The TCP socket is bound to the specified IP address `self.ip_address` and TCP port `self.tcp_port`.
- The TCP socket is set to listen for incoming connections with a backlog of 5 connections.

#### 2. UDP Socket Setup

- A UDP socket is created using the same socket module with the `socket.AF_INET` family (IPv4) and `socket.SOCK_DGRAM` type (UDP).
- The UDP socket is bound to the specified IP address `self.ip_address` and UDP port `self.udp_port`.

#### 3. Thread Creation

- Two separate threads `tcp_thread` and `udp_thread` are created using the threading module.
- The target parameter of each thread is set to point to specific methods `self.listen_tcp` and `self.listen_udp`, suggesting that these methods likely contain the logic for handling TCP and UDP communication.

#### 4. Thread Start

- Both threads are started concurrently using the start method, allowing the ECU to handle TCP and UDP communication simultaneously.

### 3.3 Example

We have provided an example demonstrating the usage of the ECU simulator in the file located at `test_ecu_simulator.py`

```
if __name__ == "__main__":
    # Create and start instances of different ECUs using the factory pattern and ↵
    ↵ abstract class
    factory = ECUFactory()

    positive_ecu = factory.create_ecu(ECUType.POSITIVE_ECU, POSITIVE_ECU_IP, ↵
    ↵ POSITIVE_TCP_PORT, POSITIVE_UDP_PORT)
    negative_ecu = factory.create_ecu(ECUType.NEGATIVE_ECU, NEGATIVE_ECU_IP, ↵
    ↵ NEGATIVE_TCP_PORT, NEGATIVE_UDP_PORT)
    # Start positive and negative ECUs
    positive_ecu.start()
    negative_ecu.start()
```

In the given example, an instance of the ECU is created in `ecu_simulator.py` by specifying the ECU's IP address, TCP port, and UDP port. Subsequently, the start method is invoked to initiate its operation.

#### Output:

```
TCP Server 172.17.0.5 listening on port 13400
UDP Server 172.17.0.5 listening on port 13400
TCP Server 172.17.0.5 listening on port 12346
UDP Server 172.17.0.5 listening on port 12347
```

Now you can execute the test by running the file located at `test_ecu_simulator.py`

```
def test_positive_ecu_simulator():
    try:
        ip = '172.17.0.5'
        ecu_logical_address = 57344

        # Create a DoIPClient instance for positive ECU simulator
        doip = DoIPClient(ip, ecu_logical_address, activation_type=None)

        # Test various interactions
        print(doip.request_diagnostic_power_mode())
        print(doip.request_entity_status())
        print(doip.request_alive_check())
        print(doip.request_activation(1))
        print(doip.get_entity())
        print(doip.request_vehicle_identification(vin="1" * 17))
        print(doip.request_vehicle_identification(eid=b"1" * 6))

    except Exception as e:
        print(f"Error during positive ECU simulation: {e}")
```

**Output:**

```

# Diagnostic power mode response
DiagnosticPowerModeResponse (0x4004): { diagnostic_power_mode : DiagnosticPowerMode.↵
↵ Ready }

# Entity status response
EntityStatusResponse (0x4002): { node_type : 1, max_concurrent_sockets : 16, ↵
↵ currently_open_sockets : 1, max_data_size : None }

# Alive check response
AliveCheckResponse (0x8): { source_address : 3584 }

# Routing activation response
RoutingActivationResponse (0x6): { client_logical_address : 3584, logical_address : ↵
↵ 55, response_code : ResponseCode.Success, reserved : 0, vm_specific : None }

# Get entity response
(('172.17.0.5', 13400), VehicleIdentificationResponse(b'19676527011956855', 3584, b'↵
↵ 11111\x00', b'222222', 0, 0))

# Vehicle identification response
VehicleIdentificationResponse (0x4): { vin: "19676527011956855", logical_address : ↵
↵ 3584, eid : b'11111\x00', gid : b'222222', further_action_required : ↵
↵ FurtherActionCodes.NoFurtherActionRequired, vin_sync_status : ↵
↵ SynchronizationStatusCodes.Synchronized }
VehicleIdentificationResponse (0x4): { vin: "19676527011956855", logical_address : ↵
↵ 3584, eid : b'11111\x00', gid : b'222222', further_action_required : ↵
↵ FurtherActionCodes.NoFurtherActionRequired, vin_sync_status : ↵
↵ SynchronizationStatusCodes.Synchronized }

```

## Chapter 4

# DoipKeywords.py

### 4.1 robotframework-doip-doipkeywords-doipdevicemanager

### 4.2 robotframework-doip-doipkeywords-doipdevice

### 4.3 robotframework-doip-doipkeywords-doipkeywords

#### 4.3.1 robotframework-doip-doipkeywords-doipkeywords-connect-to-ecu

**Description:**

Establishing a **DoIP** connection to an (ECU) within the context of automotive communication.

**Parameters:**

- `ecu_ip_address` (required, type: `str`): The IP address of the ECU to establish a connection. This should be a string representing an IPv4 address like `192.168.1.1` or an IPv6 address like `2001:db8::`.
- `ecu_logical_address` (required, type: *any*): The logical address of the ECU.
- `tcp_port` (optional, default: `TCP_DATA_UNSECURED`, type: `int`): The TCP port used for unsecured data communication.
- `udp_port` (optional, default: `UDP_DISCOVERY`, type: `int`): The UDP port used for ECU discovery.
- `activation_type` (optional, type: `RoutingActivationRequest.ActivationType`): The type of activation, which can be the default value (`ActivationTypeDefault`) or a specific value based on application-specific settings.
- `protocol_version` (optional, default: `0x02`, type: `int`): The version of the protocol used for the connection.
- `client_logical_address` (optional, type: `int`): The logical address that this **DoIP** client will use to identify itself. Per the spec, this should be `0x0E00` to `0x0FFF`. Can typically be left as default.
- `client_ip_address` (optional, type: `str`): If specified, attempts to bind to this IP as the source for both UDP and TCP communication. Useful if you have multiple network adapters. Can be an **IPv4** or **IPv6** address just like `ecu_ip_address`, though the type should match.
- `use_secure` (optional, type: `Union[bool, ssl.SSLContext]`): Enables **TLS**. If set to `True`, a default SSL context is used. For more control, a preconfigured SSL context can be passed directly. Untested. Should be combined with changing `tcp_port` to `3496`.
- `auto_reconnect_tcp` (optional, type: `bool`): Attempt to automatically reconnect TCP sockets that were closed by peer.
- `device_name` (optional, type: `str`): Name of **DoIP** device.

**Return:**

None

**Exception:**

raises `ConnectionError`: Failed to establish a DoIP connection

**Usage:**

Explicitly specifies all establishing a connection

- Connect To ECU | 172.17.0.111 | 1863 |
- Connect To ECU | 172.17.0.111 | 1863 | client\_ip\_address=172.17.0.5 | client\_logical\_add  
|
- Connect To ECU | 172.17.0.111 | 1863 | client\_ip\_address=172.17.0.5 | client\_logical\_add  
| activation\_type=0 |

### 4.3.2 robotframework-doip-doipkeywords-doipkeywords-send-diagnostic-message

**Description:**

Send a raw diagnostic payload (ie: **UDS**) to the ECU.

**Parameters:**

- `diagnostic_payload` (type: `str`): UDS payload to transmit to the ECU
- `timeout` (type: `int (s)`): send diagnostic time out (default: `A_PROCESSING_TIME`)
- `device_name` (optional, type: `str`): Name of **DoIP** device

**Return:**

None

**Exception:**

- raises `ConnectionRefusedError`: DoIP connection attempt failed
- raises `IOError`: DoIP negative acknowledgement received

**Usage:**

Explicitly specifies all diagnostic message properties

- Send Diagnostic Message | 1040 |
- Send Diagnostic Message | 1040 | timeout=10 |

### 4.3.3 robotframework-doip-doipkeywords-doipkeywords-receive-diagnostic-message

**Description:**

Receive a raw diagnostic payload (ie: **UDS**) from the ECU.

**Parameters:**

- `timeout` (optional, default: `None`, type: `int (s)`): time waiting diagnostic message.
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

- raises `ConnectionRefusedError`: DoIP connection attempt failed
- raises `IOError`: DoIP negative acknowledgement received

**Usage:**

Explicitly specifies all diagnostic message properties

- `Receive Diagnostic Message |`
- `Receive Diagnostic Message | timeout=10 |`

#### 4.3.4 robotframework-doip-doipkeywords-doipkeywords-reconnect-to-ecu

**Description:**

Attempts to re-establish the connection. Useful after an ECU reset

**Parameters:**

- `close_delay` (type: `int` (s), default: `A_PROCESSING_TIME`): Time to wait between closing and re-opening socket.
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

raises `ConnectionRefusedError`: DoIP connection attempt failed

**Usage:**

Explicitly specifies all diagnostic message properties

- `Reconnect To Ecu |`
- `Reconnect To Ecu | close_delay=10 |`

#### 4.3.5 robotframework-doip-doipkeywords-doipkeywords-disconnect

**Description:**

Close the **DoIP** client

**Parameters:**

- `device_name` (optional, type: `str`): Name of **DoIP** device

**Return:**

None

**Exception:**

- raises `ConnectionRefusedError`: DoIP connection attempt failed
- raises `ConnectionAbortedError`: close DoIP connection aborted

**Usage:**

Explicitly specifies all diagnostic message properties

- `Disconnect`

#### 4.3.6 robotframework-doip-doipkeywords-doipkeywords-await-vehicle-announcement

**Description:**

When an ECU first turns on, it's supposed to broadcast a Vehicle Announcement Message over UDP 3 times to assist **DoIP** clients in determining ECU IP's and Logical Addresses. Will use an IPv4 socket by default, though this can be overridden with the `ipv6` parameter.

**Parameters:**



- `udp_port` (optional, type: `int`): The UDP port to listen on. Per the spec this should be 13400, but some VM's use a custom one.
- `timeout` (optional, type: `float`): Maximum amount of time to wait for message
- `ipv6` (optional, type: `bool`): Bool forcing IPV6 socket instead of IPV4 socket
- `source_interface` (optional, default: `None`, type: `str`): Interface name (like "eth0") to bind to for use with IPv6. Defaults to `None` which will use the default interface (which may not be the one connected to the ECU). Does nothing for IPv4, which will bind to all interfaces uses `INADDR_ANY`.
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

- return: IP Address of ECU and `VehicleAnnouncementMessage` object
- rtype: tuple

**Exception:**

- raises `TimeoutError`: If vehicle announcement not received in time

**Usage:**

Explicitly specifies all diagnostic message properties

- `Await Vehicle Announcement`
- `Await Vehicle Announcement | timeout=10`

### 4.3.7 robotframework-doip-doipkeywords-doipkeywords-get-entity

**Description:**

Sends a `VehicleIdentificationRequest` and awaits a `VehicleIdentificationResponse` from the ECU, either with a specified VIN, EIN, or nothing. Equivalent to the `request_vehicle_identification()` method but can be called without instantiation.

**Parameters:**

- `udp_port` (optional, type: `int`): The UDP port to listen on. Per the spec this should be 13400, but some VM's use a custom one.
- `timeout` (optional, type: `float`): Maximum amount of time to wait for message
- `ipv6` (optional, type: `bool`): Bool forcing IPV6 socket instead of IPV4 socket
- `source_interface` (optional, default: `None`, type: `str`): Interface name (like "eth0") to bind to for use with IPv6. Defaults to `None` which will use the default interface (which may not be the one connected to the ECU). Does nothing for IPv4, which will bind to all interfaces uses `INADDR_ANY`.
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

- return: IP Address of ECU and `VehicleAnnouncementMessage` object
- rtype: tuple

**Exception:**

raises `TimeoutError`: If vehicle announcement not received in time

**Usage:**

- `Get Entity |`
- `Get Entity | ecu_ip_address=172.17.0.111 |`
- `Get Entity | ecu_ip_address=172.17.0.111 | protocol_version=0x02`

#### 4.3.8 robotframework-doip-doipkeywords-doipkeywords-request-entity-status

**Description:**

Request that the ECU send a **DoIP** Entity Status Response

**Parameters:**

- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

None

**Usage:**

- `Request Entity Status`

#### 4.3.9 robotframework-doip-doipkeywords-doipkeywords-request-vehicle-identification

**Description:**

Sends a `VehicleIdentificationRequest` and awaits a `VehicleIdentificationResponse` from the ECU, either with a specified VIN, EIN, or nothing.

**Parameters:**

- `eid` (optional, type: `bytes`): EID of the Vehicle
- `vin` (optional, type: `str`): VIN of the Vehicle
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

None

**Usage:**

- `Request Vehicle Identification`
- `Request Vehicle Identification | eid=0x123456789abc`
- `Request Vehicle Identification | vin=0x123456789abc`

#### 4.3.10 robotframework-doip-doipkeywords-doipkeywords-request-alive-check

**Description:**

Request that the ECU send an alive check response.

**Parameters:**

- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

None

**Usage:**

- `Request Vehicle Identification`
- `Request Vehicle Identification | eid=0x123456789abc`
- `Request Vehicle Identification | vin=0x123456789abc`

#### 4.3.11 robotframework-doip-doipkeywords-doipkeywords-request-activation

**Description:**

Requests a given activation type from the ECU for this connection using payload type 0x0005.

**Parameters:**

- `activation_type` (required, type: `RoutingActivationRequest.ActivationType`): The type of activation to request - see Table 47 ("Routing activation request activation types") of ISO-13400, but should generally be 0 (default) or 1 (regulatory diagnostics).
- `vm_specific` (optional, type: `int`): 4 byte long int
- `disable_retry` (optional, type: `bool`): Disables retry regardless of `auto_reconnect_tcp` flag. This is used by activation requests during connect/reconnect.
- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

None

**Usage:**

- `Request Routing Activation | ${0x02}`
- `Request Routing Activation | vm_specific=`
- `Request Routing Activation | vin=0x123456789abc`

#### 4.3.12 robotframework-doip-doipkeywords-doipkeywords-request-diagnostic-power-mode

**Description:**

Request that the ECU send a Diagnostic Power Mode response

**Parameters:**

- `device_name` (optional, type: `str`): Name of DoIP device

**Return:**

None

**Exception:**

None

**Usage:**

- `Request Diagnostic Power Mode`

#### 4.3.13 robotframework-doip-doipkeywords-doipkeywords-build-payload

**Description:**

Build payload

**Parameters:**

- `request` (required, type: `hex`): hex data
- `device_name` (optional, type: `str`): Name of **DoIP** device

**Return:**

return bytes data of the request

**Exception:**

- `raise ValueError: if request is None`

**Usage:**

- `Build payload by protocol version | ${request}`
- `Build payload by protocol version | hex_value`

## Chapter 5

### `__init__.py`

RobotFrameworkDoIP is a Robot Framework library aimed to provide DoIP protocol for diagnostic message.

# Chapter 6

# Appendix

## About robotframework-doip:

### *Author*

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### *Version*

0.2.0 (23.02.2026)

### *Short Description*

Robot Framework library for interacting with Electronic Control Units (ECUs)

### *Homepage*

[robotframework-doip](#)

### *Documentation*

[Readme](#)  
[Main Documentation](#)

### *Sources*

[Repository](#)

### *Issues*

[Issues](#)

### *Python required*

$\geq 3.11$

### *License*

Apache-2.0

## Chapter 7

# History

<b>0.1.0</b>	09/2023
<i>Initial version</i>	
<b>0.1.1</b>	12/2023
<i>Add ecu simulator to use for self test</i>	
<b>0.1.2</b>	4/2024
<i>Update the documentation for DoIP</i>	
<b>0.1.3</b>	4/2024
<i>Publish package to PyPi</i>	
<b>0.1.4</b>	4/2024
<i>Add dependency for package</i>	
<b>0.1.5</b>	10/2024
<i>Add feature that supports working with multiple connections</i>	
<b>0.1.6</b>	3/2025
<i>Add feature that supports sending diag message without waiting any response</i>	
<b>0.2.0</b>	02/2026
<i>Usage of Setuptools replaced by usage of PIP/TOML/Setuptools</i>	

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