

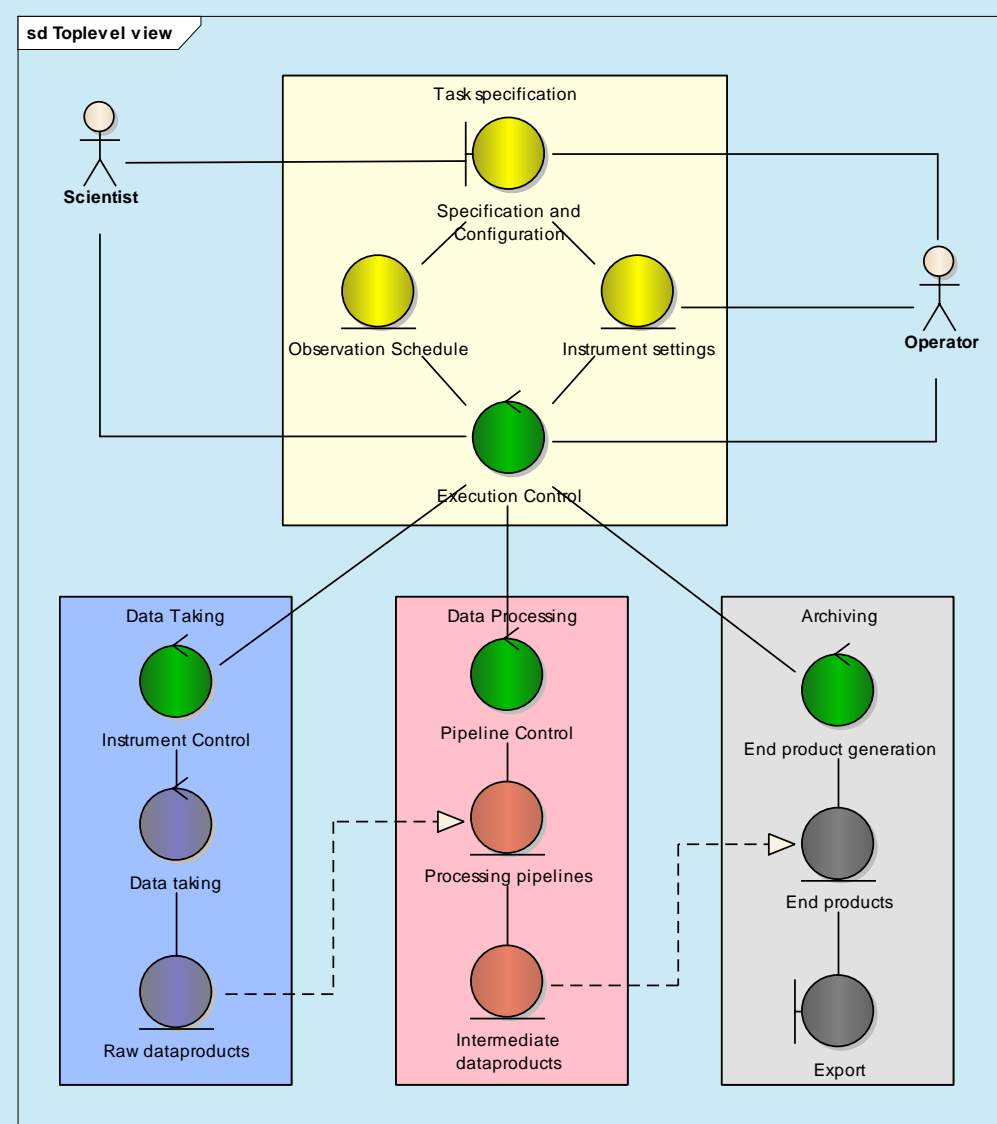
Monitoring & Control Software for the new Westerbork Phased-Array Feed System



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System Overview

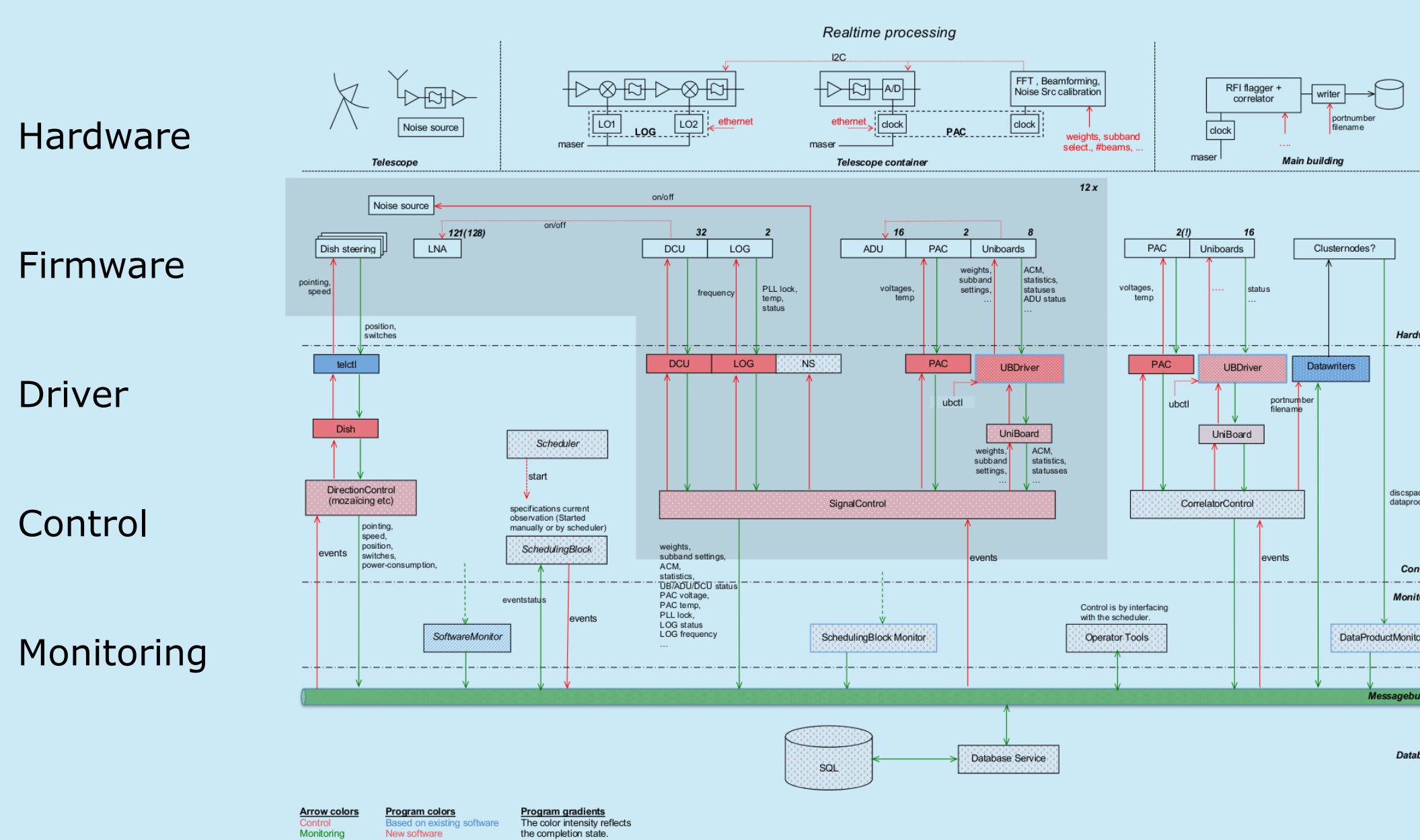
From a software point-of-view



- **Task Specification**
 - Schedule observations
- **Data Taking**
 - Write raw UV-data
- **Data Processing**
 - Calibration & Imaging
- **Archiving**
 - Data Quality & Ingest
- **Monitoring and Control**

Monitoring & Control

Layered Design



Controllers

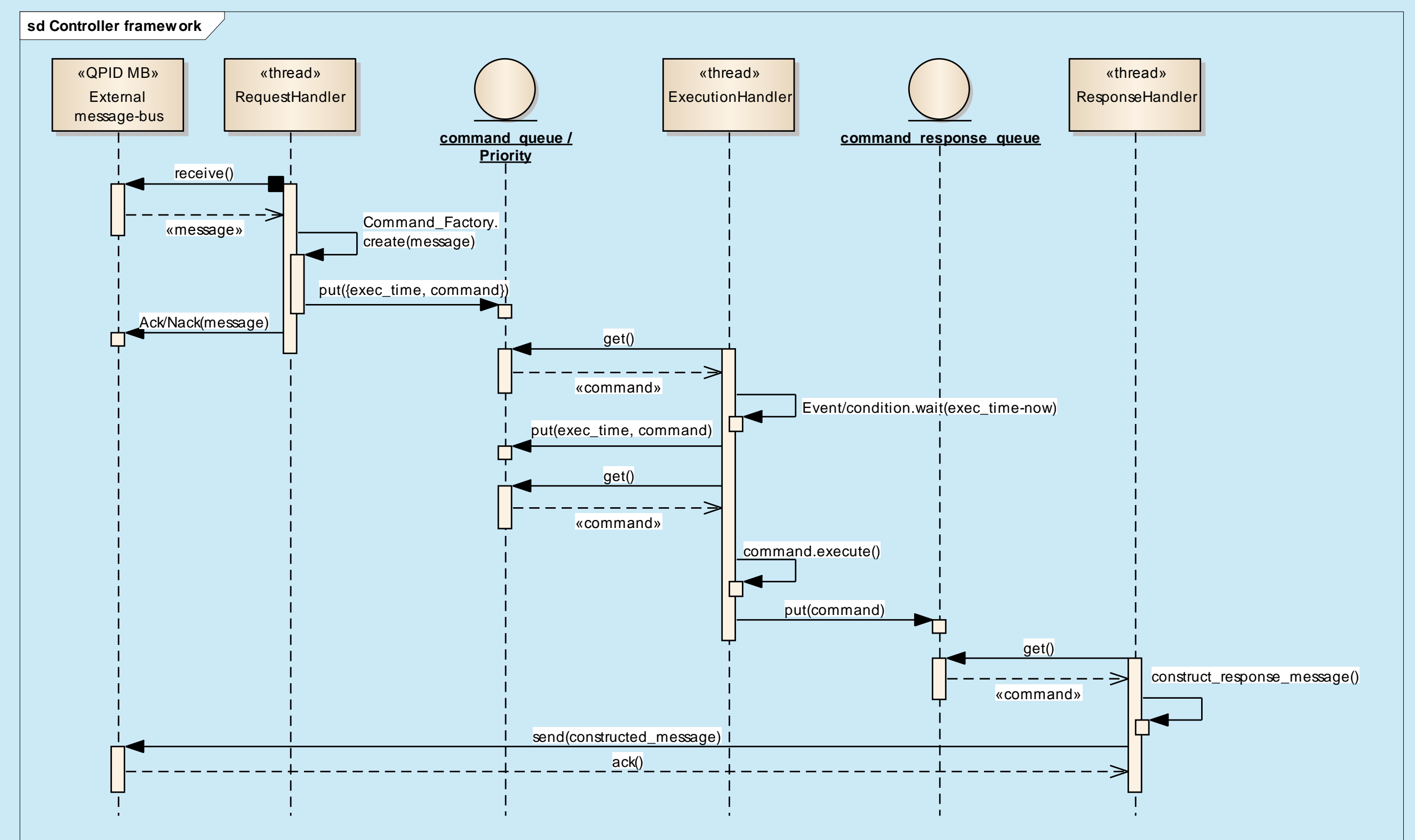
- Handle commands that arrive via the Message Bus
- Serialize access to the Drivers
- High-Level commands
 - Are user- or task-oriented
 - Are typically sent to the *whole system*
 - Examples: "Start Observation", or "Calibrate PAF"
- Low-Level commands
 - Are subsystem- or driver-oriented
 - Are typically sent to one *sub-system*
 - Are often sub-system specific
 - Examples: "set_vamp", "set_vcoax", "get_status"

Drivers

- Drivers interface with (custom-made) hardware
- Interface definition: wire protocol
- Written in Python
 - UniBoard has low-level C++ driver to meet performance requirements

Monitoring & Control

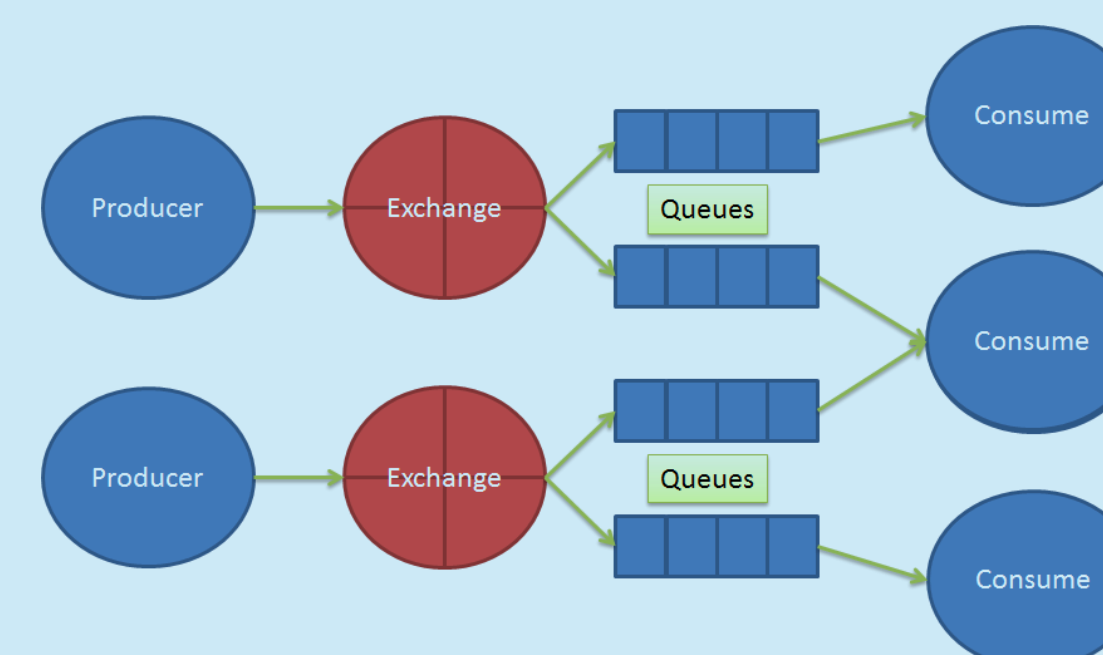
Controller Framework



- Controller Framework handles three main tasks any controller must do:
- Reception and execution (at the right time) of commands received over the message bus
 - Guarantee that commands are not mixed (executed in sequence)
 - Publish a configurable set of status information at regular intervals

- **RequestHandler**
 - Listen for new message on the message bus
 - Turn messages into command objects
 - Put commands in command queue
- **ExecutionHandler**
 - Wait for new commands in command queue
 - Handle scheduling and execution of commands
 - Put command responses into response queue
- **ResponseHandler**
 - Listen for responses in response queue
 - Construct response message
 - Send response message to the message bus

Message Queues



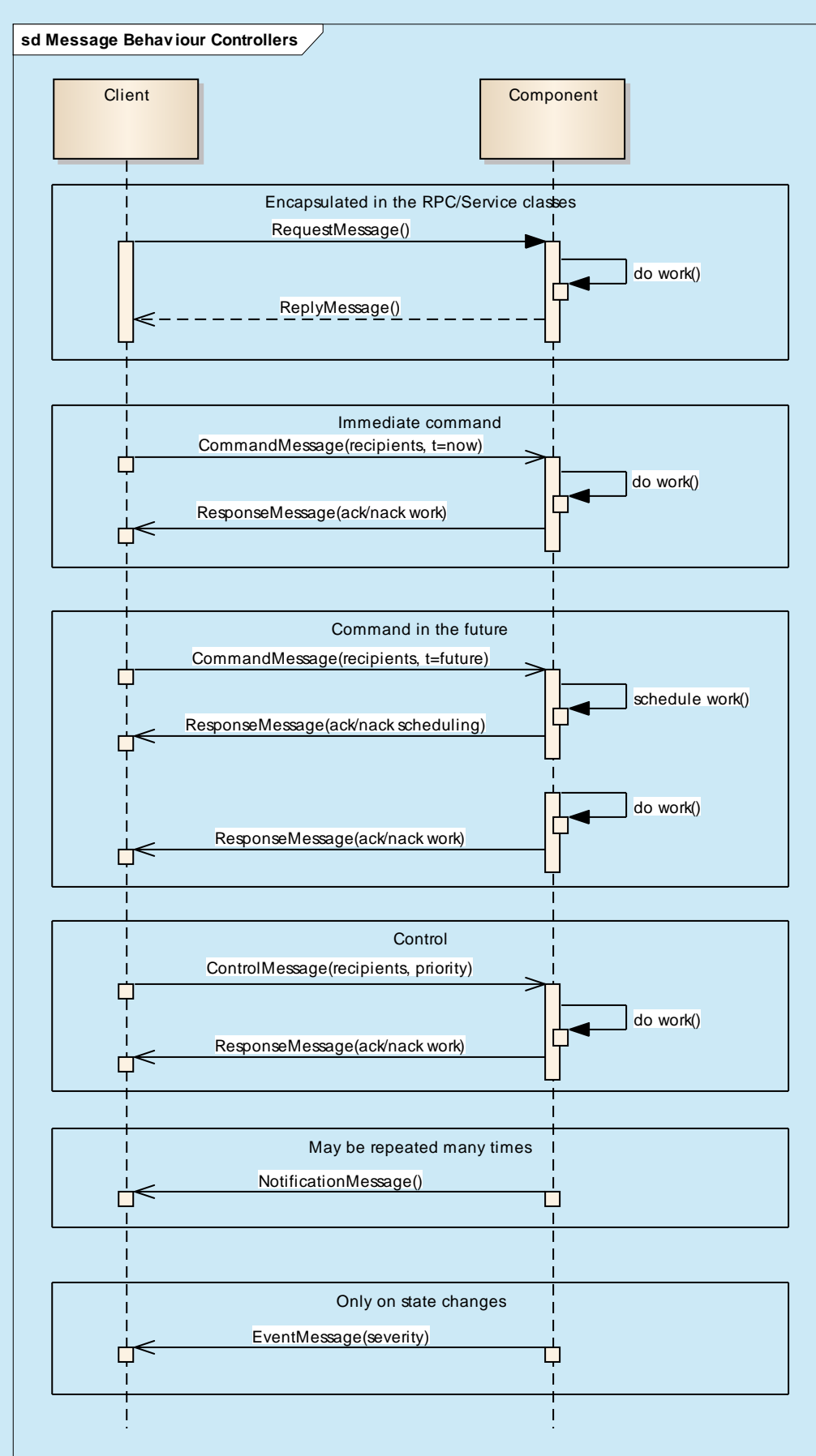
- Advantages of Message Queuing
- Reliable communication, guaranteed delivery
 - Ease of use: simply post a message to an exchange
 - Routing is run-time configurable
 - Eases loose coupling of system components

For APERTIF we chose to use AMQP

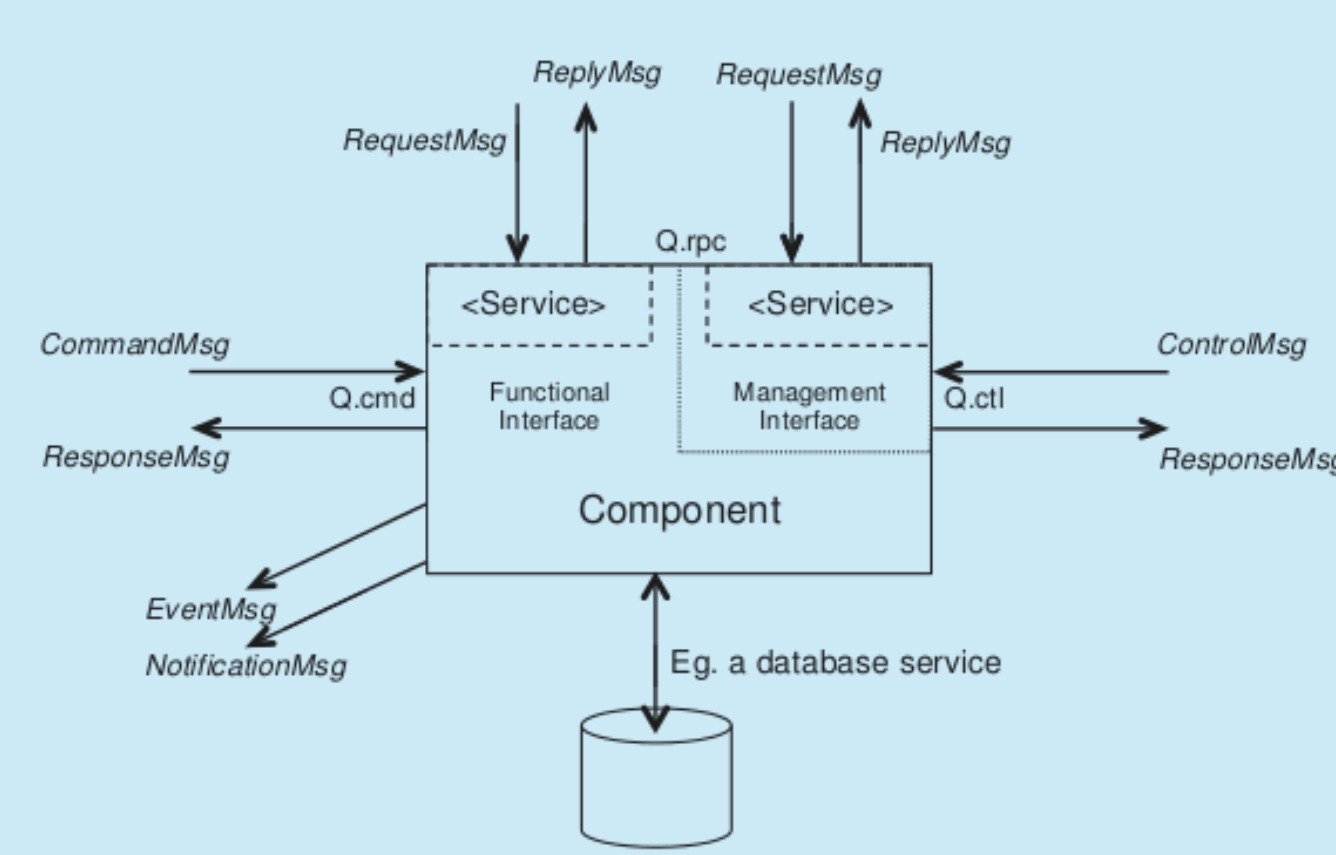
- Advanced Message Queuing Protocol (AMQP)
 - Based on IEEE standard (ISO/IEC 19464)
- Apache Qpid
 - Messaging built on AMQP
 - C++ and Python bindings
 - Also used by LOFAR
 - Ubuntu PPA (deb <http://ppa.launchpad.net/qpid/released/ubuntu/trusty/main>)
- Wrapped Qpid in C++ library & Python module
 - Eases send & receive of messages ("ToBus" and "FromBus")
 - Classes like CommandMessage, EventMessage, NotificationMessage, etc.

Software Components

Behavior of a component

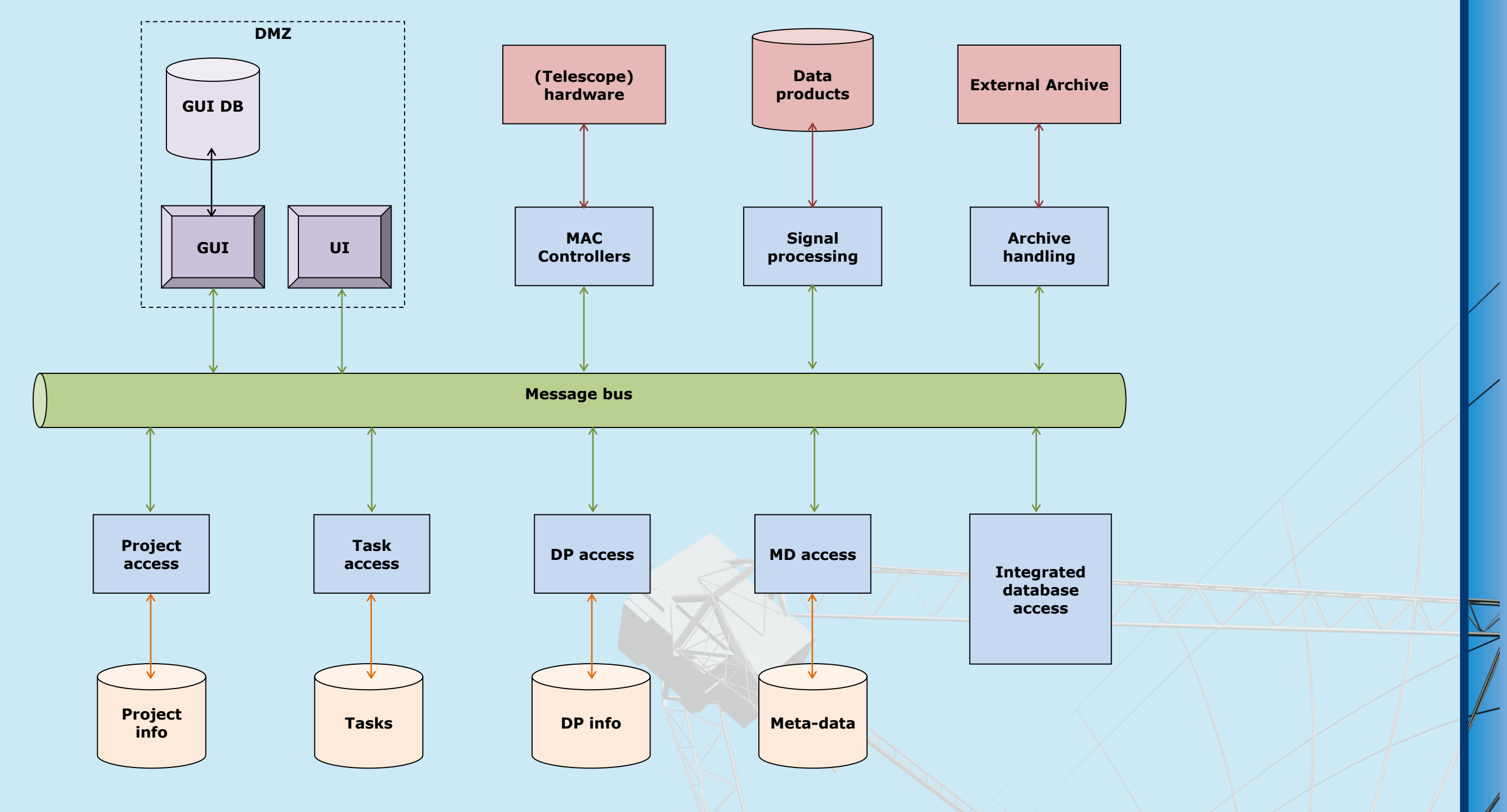


Interfaces of a component



Communication with components

	Synchronous	Asynchronous
Functional	<p>Communication: RPC calls (p2p) Messages: Request/Reply Queue name: .rpc Purpose: User interface to RPCs E.g. low level commands to the controllers, database access, etc.</p>	<p>Communication: Commands (scatter/gather) Messages: Command/Response Queue name: .cmd Purpose: User interface to multiple components with asynchronous answer E.g. high level commands</p>
Management	<p>Communication: RPC calls (p2p) Messages: Request/Reply Queue name: .rpc Purpose: Ask about health or behaviour of the component E.g. queries about counters, performance, etc.</p>	<p>Communication: Control (p2p) Messages: Control/Response Queue name: .ctl Purpose: Change behaviour of component E.g. shutdown, start/stop/set Notification sending, suspend/resume RPC queue, etc.</p>



Message Routing

- Broker daemon on every host
- Routing configuration tool
- Single exchange: "APERTIF"
- Routing based on subject
- Destination queues for each component

```
# Routing configuration for APERTIF
# Use the tool 'config_routing' to apply this table
[system]
name=APERTIF

[routes]
# APERTIF Routing tables
#
# routingkey destinations
control: SignalControl.ctl, DirectionControl.ctl
command: SignalControl.cmd, DirectionControl.cmd
response: SignalControl.notification, DirectionControl.notification
```

