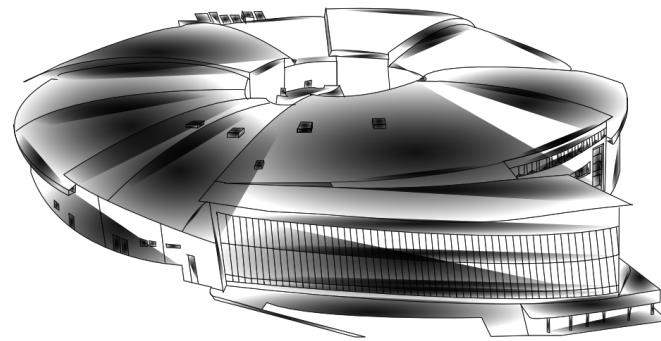


Taurus: Big & Small

from Particle Accelerators to Desktop Labs



by: Carlos Pascual-Izarra

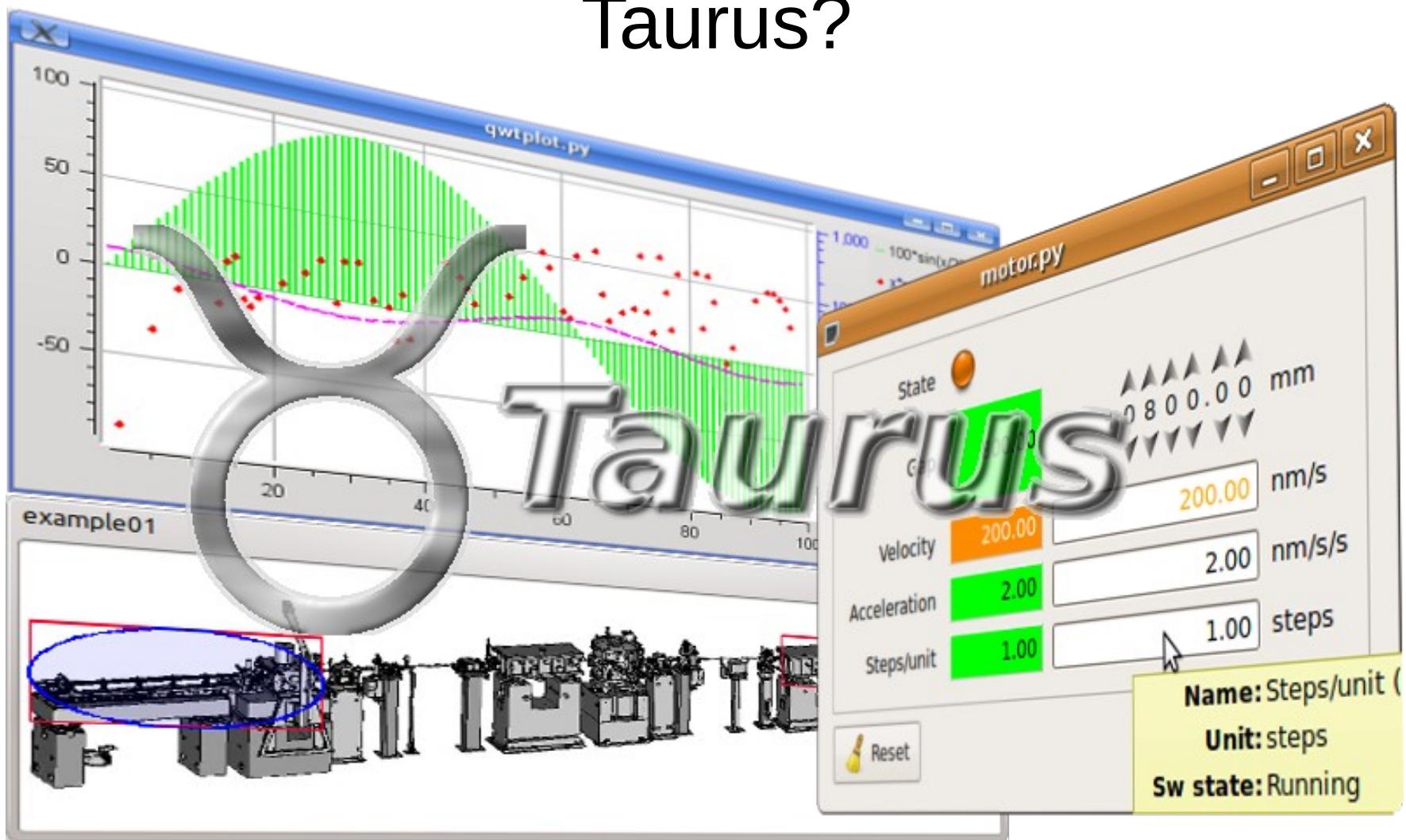
+ G. Cuní, C. Falcón-Torres, D. Fernández-Carreiras, Z. Reszela, M. Rosanes, Oscar Prades-Palacios



ICALEPCS2017



Taurus?



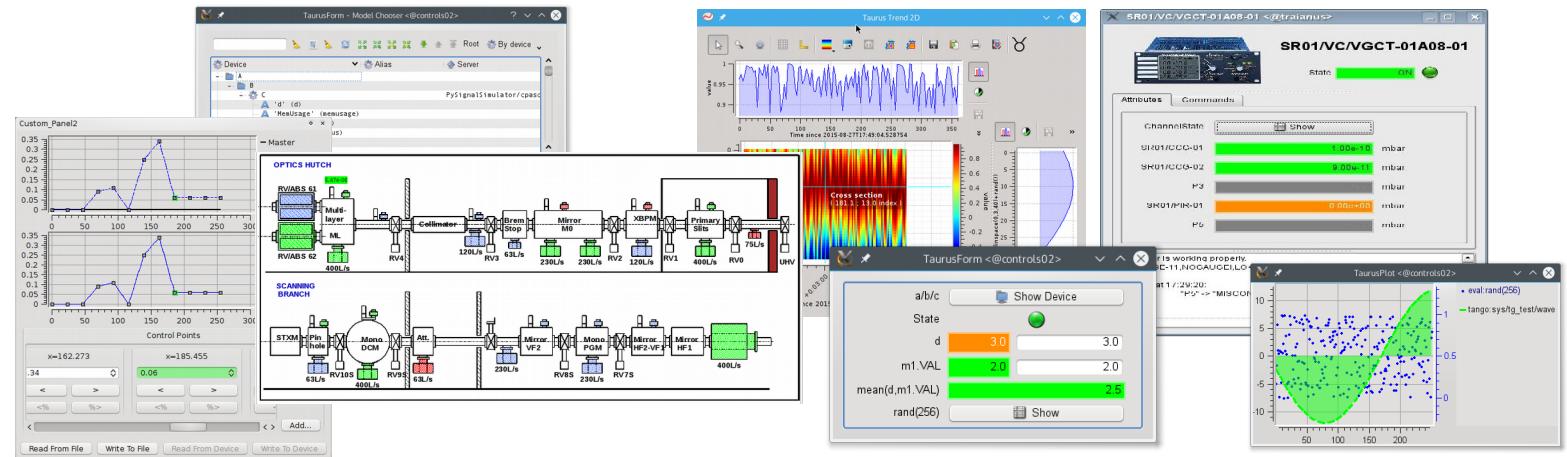
- **Taurus** is a framework for building control and data acquisition **CLIs** and **GUIs**
- It is based on **Python** and extends **PyQt**
- It supports plugins for various control systems (**Tango**, **EPICS**,...) or data sources (**HDF5**, **Python eval**,...)



<https://taurus-scada.org>

Structure of Taurus

Taurus Qt Widgets



Model Objects

model

model

model

model

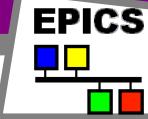
model

model

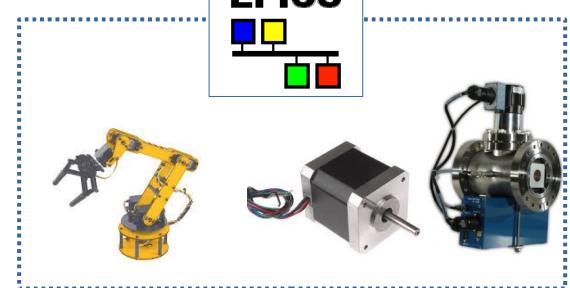
model

Taurus Core

Scheme plugins



Data Sources



Approaches to interface with unsupported sources

e.g., how to read data from a HDF5 file as an attribute?



Distributed Control System

Find (or write a new) DS capable of exposing contents of an hdf5 file as a Tango attribute...

Custom scheme

Use the custom h5file scheme plugin

```
h5file:/tmp/foo.h5::entry/time
```

```
eval:@f=h5py.File("/tmp/foo.h5")/f["entry/time"][:]
```

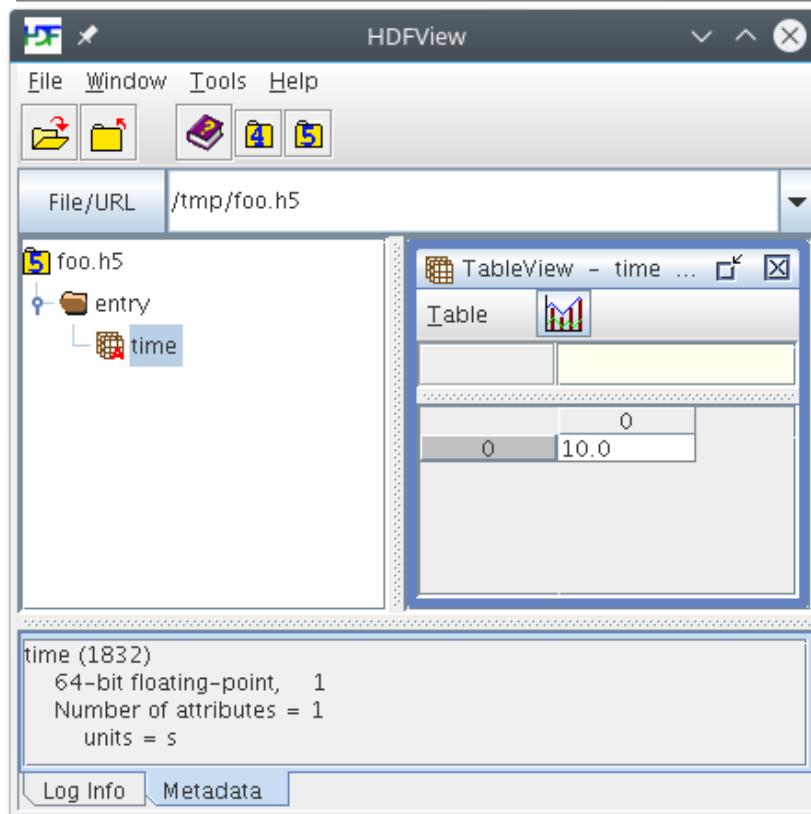
Evaluation scheme

Use the eval scheme with the h5py module



h5file scheme

```
$> pip install git+https://github.com/taurus-org/h5file-scheme.git  
$> echo 'EXTRA_SCHEME_MODULES = ["h5file"]' >> taurus/tauruscustomsettings.py  
$> taurusform h5file:/tmp/foo.h5::entry/time \  
    tango:sys/tg_test/1/ampli \  
    eval:{tango:sys/tg_test/1/ampli}/{h5file:/tmp/foo.h5::entry/time}
```



Eval scheme

- Allows mathematical evaluations
- Support writable eval attributes
- Use **any module or class as a custom evaluator**



```
$> taurusform 'eval:@c=mymod.MyClass()/c.foo' \
    'eval:@datetime.*/date.today().isoformat()' \
    'eval:@os.*/environ["TANGO_HOST"]' \
    'eval:@os.path.*/getsize("/var/log/boot")<50'
```

mymod.py

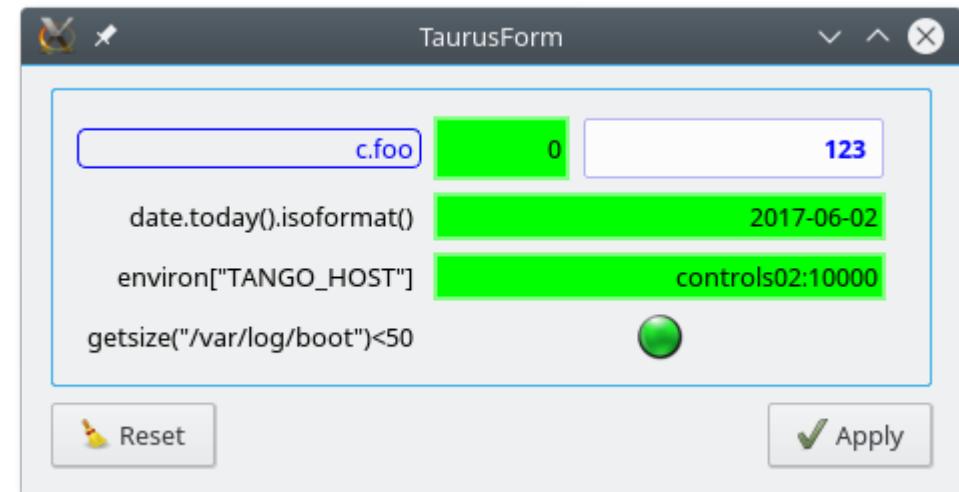
```
class MyClass(object):

    _foo = 0

    def get_foo(self):
        return self._foo

    def set_foo(self, value):
        self._foo = value

    foo = property(get_foo, set_foo)
```

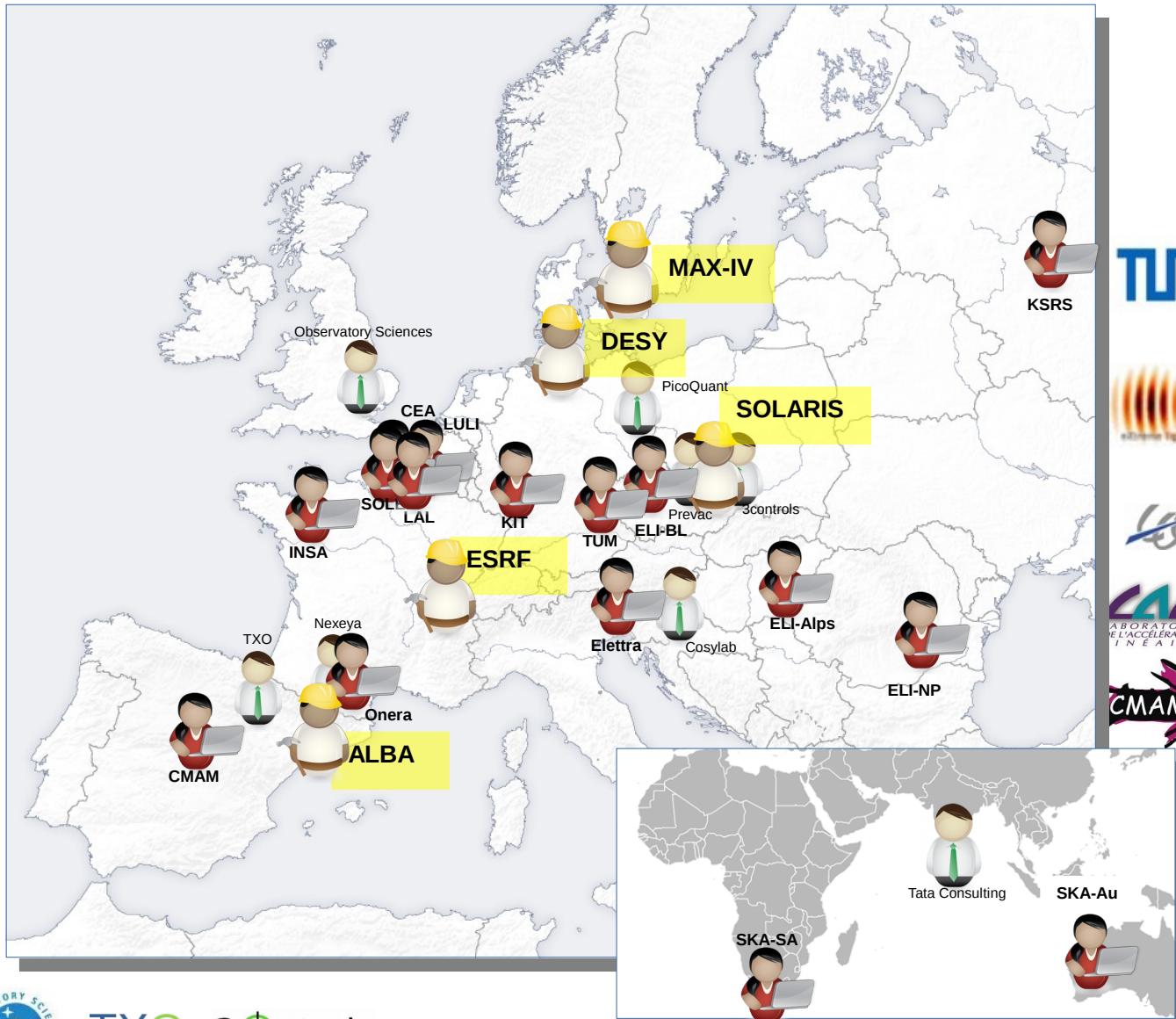


docs: <http://www.taurus-scada.org-devel/api/taurus/core/evaluation.html>
mymod example: taurus.core.evaluation.test.res.mymod

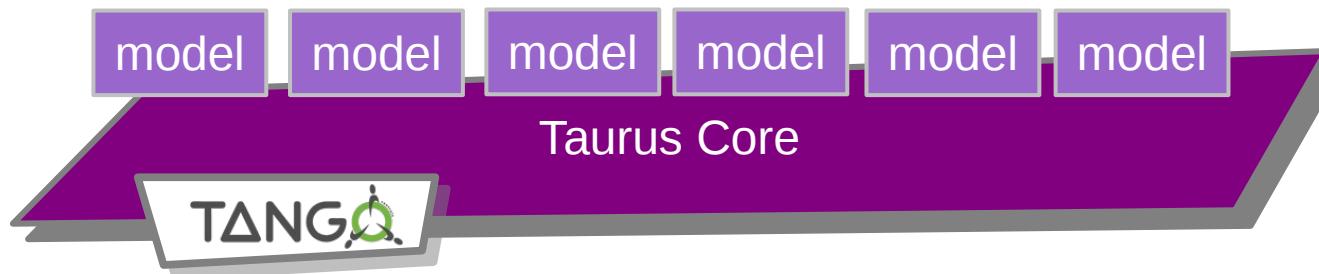
Taurus in large facilities



Taurus Community



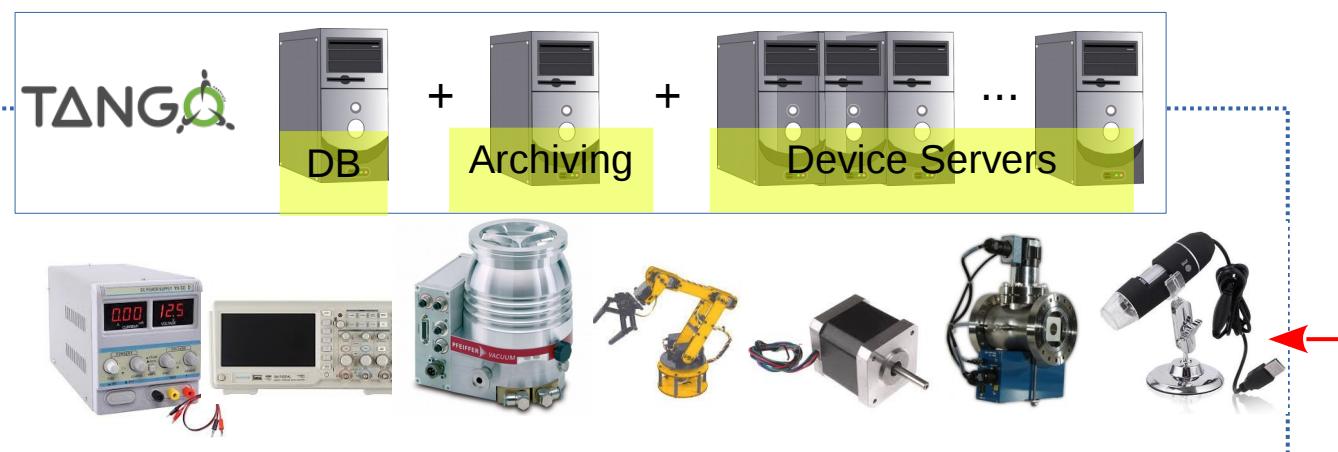
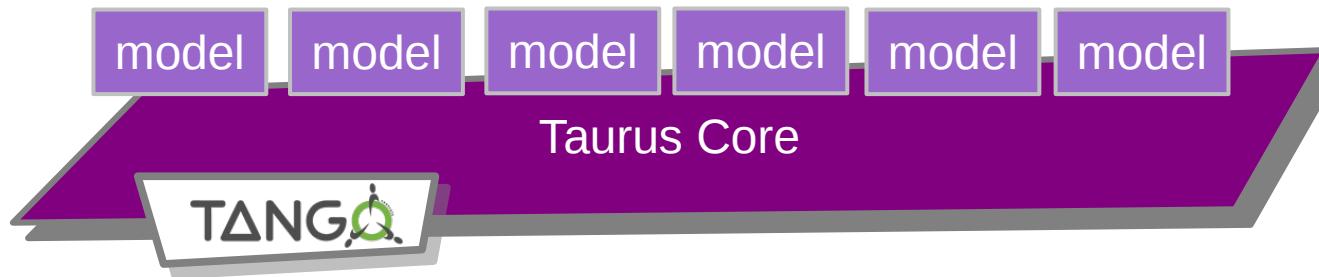
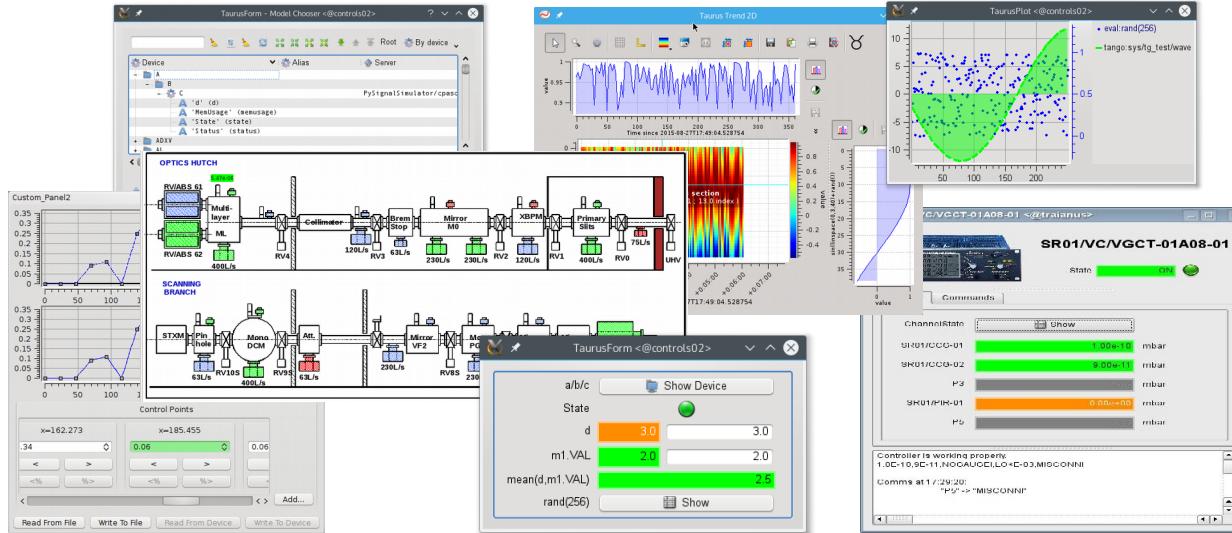
Taurus in large Facilities: example of ALBA



- Most of the control system relies on Tango
- ~100 Taurus GUIs
- ~300 machines
- ~10 Tango DBs
- ~100K Tango attributes
- New hardware ?

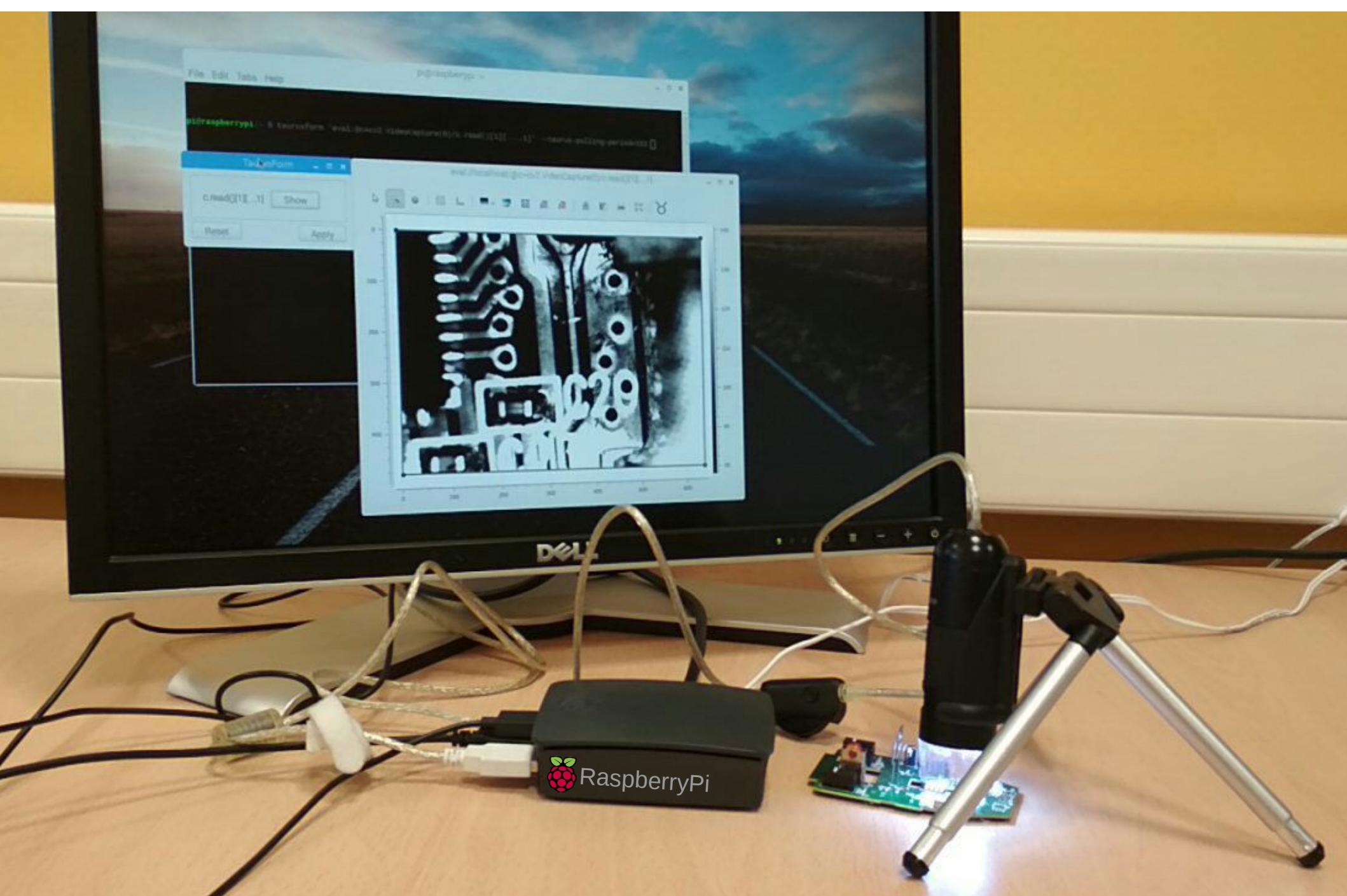


Taurus in large Facilities: example of ALBA

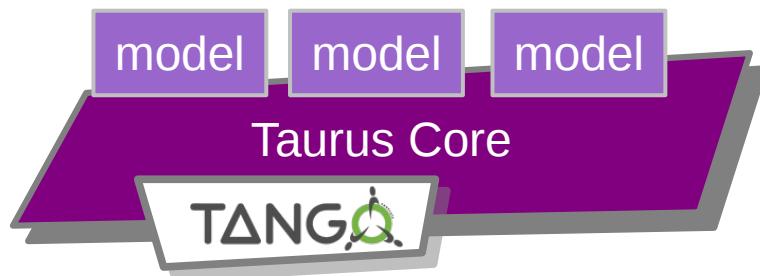
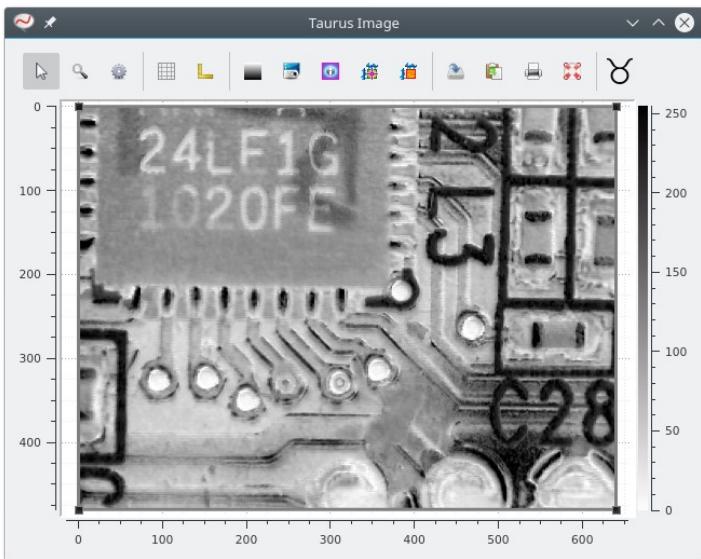


- Most of the control system relies on Tango
- ~100 Taurus GUIs
- ~300 machines
- ~10 Tango DBs
- ~100K Tango attributes
- New hardware → write a Tango Device Server

Taurus in “Desktop Labs”:



Taurus in “Desktop Labs”



Approach 1

*Use same tools as for large facilities (scale-down):
use a Distributed Control System on a single
machine*

- Install Taurus + Tango on a single machine:

```
$> apt-get install default-mysql-server  
$> apt-get install tango-db  
$> apt-get install python-taurus
```

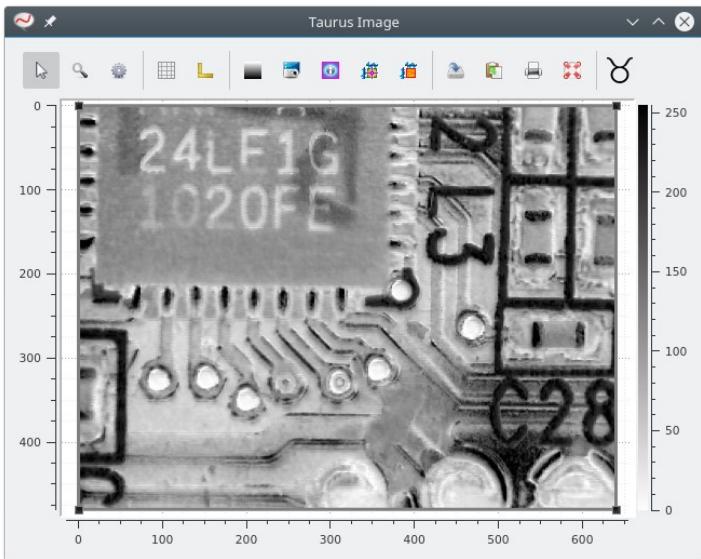
- Install, configure and run a Device Server supporting your hardware (or write a new one)

Recommended if:

- you are already familiar with Tango/EPICS
- the hardware is already supported by Tango/EPICS
- you do not mind the communication overhead



Taurus in “Desktop Labs”

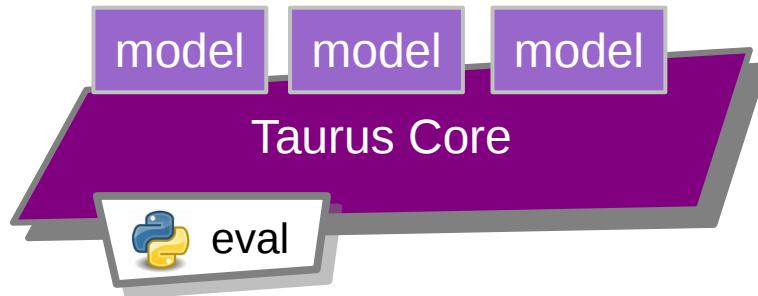


Approach 2

Use the eval scheme and connect directly

```
$> apt-get install python-taurus
```

```
$> taurusimage 'eval:@c=cv2.VideoCapture(0)/c.read()[1][...,1]'
```



Recommended for:

- single-machine systems
- quick prototyping
- quick support of new hardware





<https://taurus-scada.org>

Welcome to Taurus Home Page!

Docs » Welcome to Taurus Home Page!

Edit on GitHub

Welcome to Taurus Home Page!

The screenshot shows the Taurus software interface. On the left, there is a large Taurus logo and a search bar labeled "Search docs". Below the search bar are links to "Home Page", "Project Page", "Download from PyPI", and "Taurus 4.1 documentation". At the bottom, there are links to "Read the Docs" and a dropdown menu set to "v: latest".

The main area displays two windows. The left window is titled "example01" and contains a plot with a green shaded region and red data points. The right window is titled "motor.py" and shows a control panel with sliders for Velocity (200.00), Acceleration (2.00), and Steps/unit (1.00). The "Steps/unit" slider has a tooltip: "Name: Steps/unit (Unit: steps Sw state: Running)". A "Reset" button is also visible.