

'Busy' Record, Put-callback Support

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Feb. 2022

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Basic Automation Example

1. Move motor to some position

Has the motor
reached the position?

2. Open shutter

How quickly does
the shutter open?

3. Take data for 5 seconds

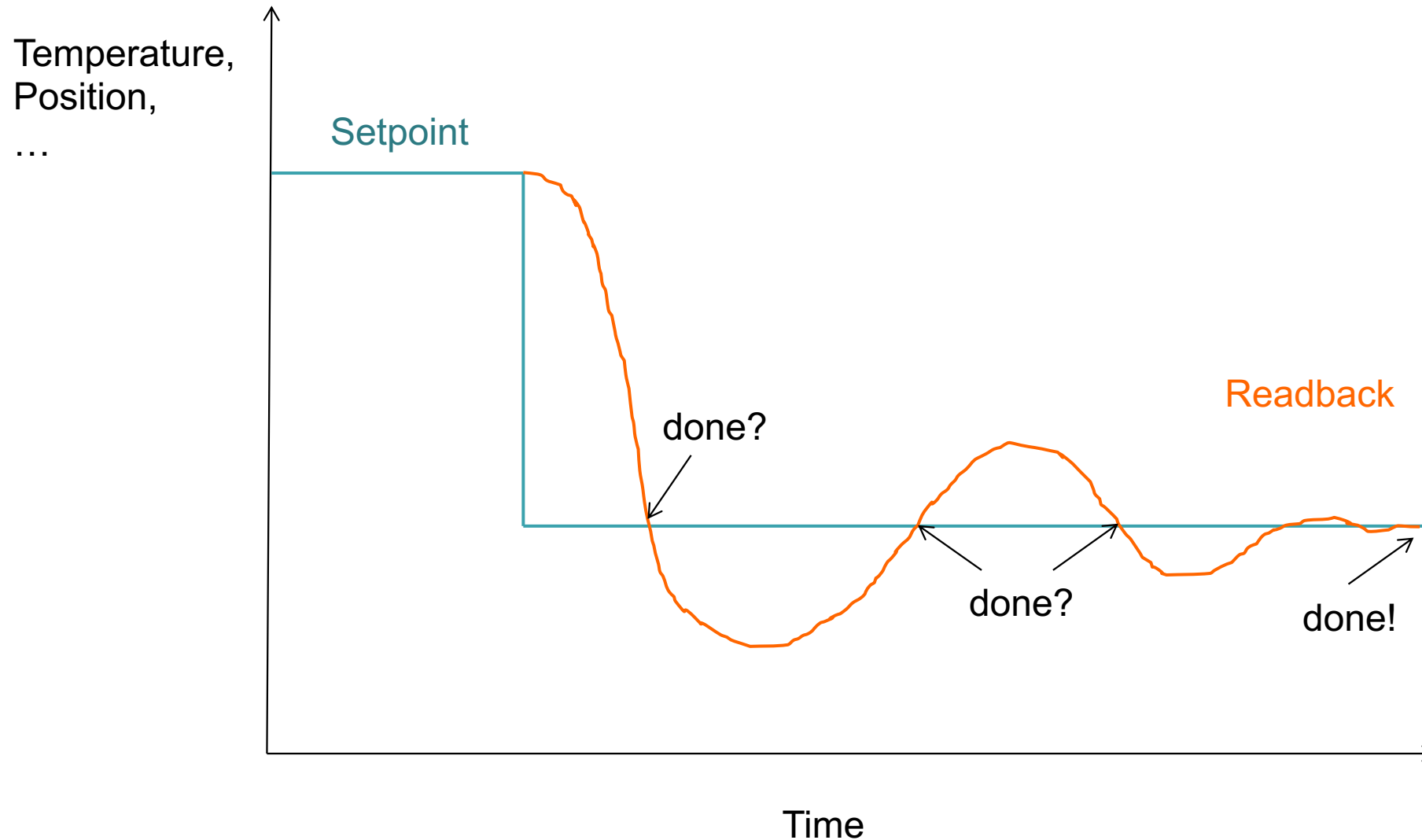
4. Close shutter

What not to do

1. Ask motor to move to position X
2. Wait until motor encoder reports $X \pm 0.1 \text{ mm}$
3. Ask shutter to open
4. Wait 4 seconds - Fred said that's how long it'll take
5. Take data for 5 seconds
6. Close shutter

Not reliable!

Based on readback, are we done?



IOC has to tell us when it's done

1. Use CA “put-callback”
2. Record completes callback when its “done”

Requires record with support for “completion” aka “put-callback”

- Motor record: When reaching desired position
- General record: Check device support manual
- Plain database: Use BUSY record

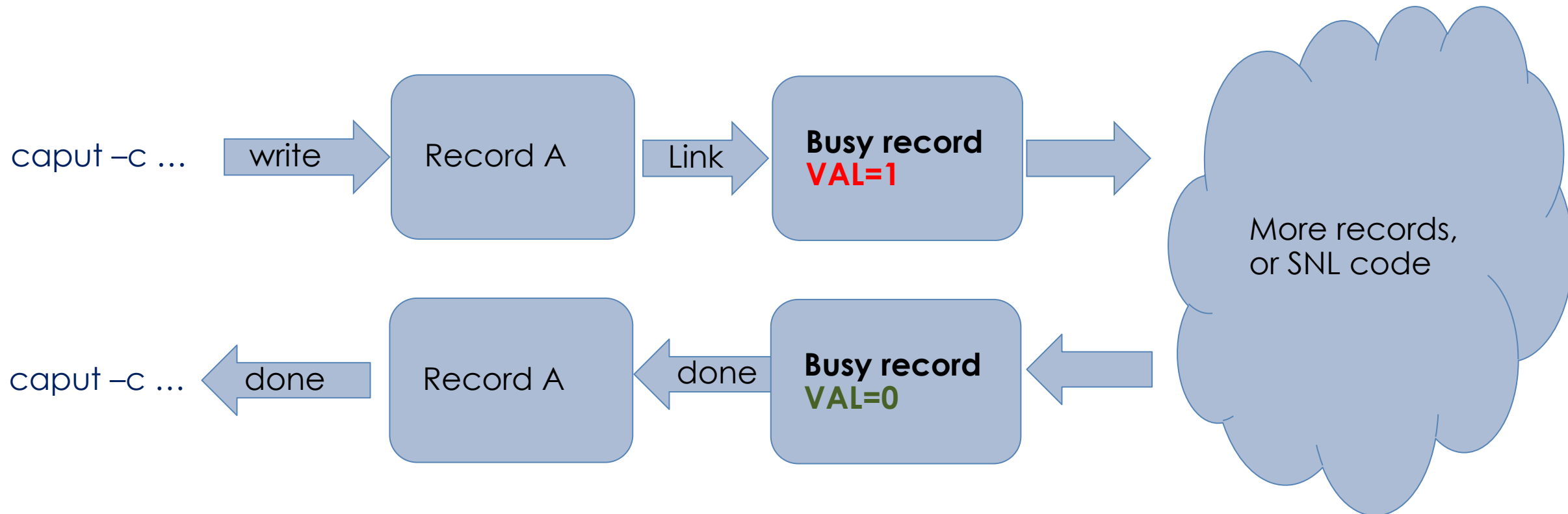
EPICS record PACT field

- PACT is binary flag that is 1 (ON) when record is processing
- CA put-callback is mechanism to use PACT information...
- ...and not return until PACT is 0 (OFF)

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caput -c -w <timeout> <PV>
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BUSY record

- VAL = 1 "Busy", VAL=0 "Done"
- Blocks processing (PACT=1) while busy



Typical Use

- Writing to some record, which has FLNK or OUT links to a busy record, sets the busy.VAL = 1
- This causes writer to that first record to block in put-callback
- Something else resets busy.VAL = 0
 - a) Other database logic
 - b) Sequencer code
 - c) asyn device support
 - d) ...
- Put-callback completes

Put-Callback

.. Is essential for robust automation

Use BUSY record to create database logic that supports put-callback