

# CA Nimsoft Monitor

## Probe Guide for Controller controller v7.0 series



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## Documentation Changes

This table describes the version history for this document.

<b>Version</b>	<b>Date</b>	<b>What's New?</b>
7.1	December 2013	Version number change only for documentation; no GUI changes for this release.
7.0	September 2013	Updated for NMS 7.0
5.9	June 2013	Online help restructured for consistency with other probe documentation
5.7	June 2012	Initial web-based GUI for this probe.

# Chapter 1: Overview

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The controller is a core component of the Nimsoft robot and is responsible for scheduling the other probes and maintaining contact with the Nimsoft hub.

The controller probe focuses on keeping configured probes running according to the probe configuration and handles 'housekeeping' operations towards Nimsoft, such as telling the hub about its state, name-lookup services, license management, etc. It responds to the elements in the configuration files *robot.cfg* and the *controller.cfg* as well as to commands requested over the registered port TCP/48000.

Important! We do not support cloning of robots. We recommend you use the cloud installation option for the robot to ensure that it is not started until the vm-clone instance is created, and then using *request.cfg* to install the required probes and probe configurations. For more information see [http://docs.nimsoft.com/prodhelp/en\\_US/Monitor/6.5/NimsoftMonitorServerInstallationGuide/NimBUSWindowsRobot.html](http://docs.nimsoft.com/prodhelp/en_US/Monitor/6.5/NimsoftMonitorServerInstallationGuide/NimBUSWindowsRobot.html)

This section contains the following topics:

[About This Guide](#) (see page 7)

[Related Documentation](#) (see page 7)

[Release Summary](#) (see page 8)

## About This Guide

This guide is for the CA Nimsoft Monitor Administrator to help understand the configuration of the Controller probe.

## Related Documentation

For related information that may be of interest, see the following material:

### Related Documentation

Documentation for other versions of the controller probe

The [Release Notes](#) for the controller probe

[User documentation for the Admin Console](#)

*Monitor Metrics Reference Information for CA Nimsoft Probes*

([http://docs.nimsoft.com/prodhelp/en\\_US/Probes/ProbeReference/index.htm](http://docs.nimsoft.com/prodhelp/en_US/Probes/ProbeReference/index.htm))

## Release Summary

Please refer to the [Nimsoft Compatibility Support Matrix](#) for the latest information on supported platforms. See also the [Support Matrix for Nimsoft Probes](#) for additional specific information on the controller probe.

# Chapter 2: Configuration Details

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This section contains configuration details specific to the Controller Probe.

**Navigation:** controller

Set or modify the following values based on your requirement:

**controller > Probe Information**

This section provides the basic probe information and is read-only.

**controller > Hub Connectivity**

This section provides the hub information and is read-only.

**controller > General Configuration**

This section provides general configuration details.

- Identification property User Tag 1: User defined tag used as a grouping/locating mechanism.  
Default: blank
- Identification property User Tag 2: User defined tag used as a grouping/locating mechanism.  
Default: blank
- Log Level: Sets the amount of detail to be logged to the log file. Log as little as possible during normal operation to reduce disk consumption, and increase the level of detail when debugging.  
Default: 0 - Fatal
- Log Size (KB): Allows you to change the size of the log file according to your needs. When the log file size is reached, new entries are added and the oldest log file entries will be deleted.  
Default: 1024 KB
- Hub update interval (minutes): Determines at what interval the hub is contacted with an "alive" message. The range is 1 to 180 minutes. Note that the hub is notified on a shorter interval when changes occur in the probe list.
- On Robot uptime, reported as state changes: If this option is selected, QoS messages on robot uptime will be sent. The QoS message 'status = up' will be sent when the robot starts, and the QoS message 'status down' will be sent when the robot stops.
- Set QoS source to robot name instead of computer host name: Select this option to use the robot name for the QoS source when sending alarms. Otherwise the host name of the computer hosting a probe is by default used as QoS source in QoS message from the probes.  
Default: Disabled.

**controller > Status**

This section provides the status of the robot and is read-only.

This section contains the following topics:

[Setup Configuration Details](#) (see page 12)

## Setup Configuration Details

This section contains configuration details specific to the Controller Probe.

**Navigation:** controller > Setup

Set or modify the following values based on your requirement:

### Setup > Nimsoft

- Robot Name: Displays the name of the robot where this probe resides.  
Default: Auto Detect (Recommended)
- Secondary Hub Robot Name: Defines the method used to determine the secondary hub. The secondary hub will be used if the primary hub is unavailable.  
Default: Auto Detect (Recommended)
- Search the subnet for a temporary hub when primary and secondary hubs are unavailable : Select this option to enable the Robot Process and Port Controller to search the internet for a temporary hub.  
Default: not selected

### Setup > Advanced

- Automatically unregister from HUB at shutdown: When the robot is stopped, an unregister message is sent to the hub on which it is registered. This will make the robot disappear from Infrastructure Manager. If this is not selected, the stopped robot will appear with a red icon, enabling the operator to detect the situation.
- Suspend all probes when no network connection is available: When running the robot on a computer with no network connection, you can determine whether the robot should be active or enter a sleep mode where all probes are suspended until a network connection is again available. If this option is not selected the alarm messages will be spooled and flushed when a network connection is again available.  
**Note:** This function is available only on Windows platforms.  
Default: selected (Recommended)  
Configuration file locking: Locks the configuration.
- First Probe port number: Daemon type probes will normally register a command port, which is allocated run-time on probe start-up. Setting the probe port number will make the robot allocate specific port numbers for the probes as they are started. Use this option if you want the probes to have port numbers in a specific range for router / firewall purposes.
- Time offset from UTC (override the local time zone setting) sec: Overrides the local time zone setting. The time specification must be entered as time offset from UTC (in seconds).

- When no contact with hub: Set limitations for attempts to connect an unmanaged robot (a robot that has lost the contact with the hub) to a hub.  
Default: Allow move only within domain (Recommended)

#### Setup > Environment Variables

- Variable Name: Environment variable for your NMS system. This variable is inherited by all the probes managed by this robot.
- Variable Value: The value assigned to the variable name.

#### Setup > Alarms

- Probe restart when the probe does not respond: Select the alarm to be sent when a probe is not responding and is restarted.
- Dispatch error (internal): Select the alarm to be sent when there is a dispatch error for the probe.
- Max restart attempts reached for the probe: Select the alarm to be sent when the maximum restart attempts have been reached.
- Error starting probe: Select the alarm to be sent when there is an error starting the probe.
- Timed probe did not return 0 on termination: Select the alarm to be sent when the probe does not return a value of 0.
- Probe unregisters port but keeps running: Select the alarm to be sent when the probe unregisters the port but continues to run.
- Probe distribution request error: Select the alarm to be sent when there is an error during probe distribution.
- Distribution post-install error: Select the alarm to be sent when there is an error after the probe is distributed and installed.
- Time interval at which alarm will be resent (minutes): Select the length of time (in minutes) when an alarm will be resent.

#### Setup > Virtual

The Controller probe sets up the communication between the robot and the virtual probe running a remote probe.

**Important! The Netware System probe is the only probe that can be set up on a virtual robot.**

- Virtual Robot: The name of the machine where the netware probe is installed and running.
- User tag 1: A user defined tag for this virtual robot.
- User tag 2: A user defined tag for this virtual robot.

Virtual robots, using the proxy probe, will be created for 'remote' probes. remote probes are installed and running on computers without a robot. The remote probe is configured with the path to the robot.

### Setup > NAT

You can allocate an external IP address to a robot that resides on another IP network with incompatible addressing using Network Address Translation. The robot will be able to send alarms and QoS messages, but the hub will not be able to communicate back to the robot.

When Network Address Translation (NAT) is in effect between the robot and the hub, the robot must be configured to provide the correct address to the hub. All communication from the hub to the robot will use this address. NAT can be set for the primary and secondary hubs.

- IP of the Robot as seen from the primary hub: Enter the name of the robot as shown in the primary hub configuration.
- IP of the Robot as seen from the secondary hub: Enter the name of the robot as shown in the secondary hub configuration.

### Setup > IP

- Robot IP Address: Select the option for detecting the IP address, either automatically detect or enter a specific hub address.
- IP version support: Select the IP version support for the robot.
- Local IP validation: Select this option if you want local IP validation performed.

### Setup > Data origin

- Origin: Enter the origin name you would like associated with this robot.
- Update button: Click this button to update the origin name associated with this robot.