

Package ‘crew’

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Title A Distributed Worker Launcher Framework

Description In computationally demanding analysis projects, statisticians and data scientists asynchronously deploy long-running tasks to distributed systems, ranging from traditional clusters to cloud services. The ‘NNG’-powered ‘mirai’ R package by Gao (2023) <[doi:10.5281/zenodo.7912722](https://doi.org/10.5281/zenodo.7912722)> is a sleek and sophisticated scheduler that efficiently processes these intense workloads. The ‘crew’ package extends ‘mirai’ with a unifying interface for third-party worker launchers. Inspiration also comes from packages. ‘future’ by Bengtsson (2021) <[doi:10.32614/RJ-2021-048](https://doi.org/10.32614/RJ-2021-048)>, ‘rrq’ by FitzJohn and Ashton (2023) <<https://github.com/mrc-ide/rrq>>, ‘clustermq’ by Schubert (2019) <[doi:10.1093/bioinformatics/btz284](https://doi.org/10.1093/bioinformatics/btz284)>, and ‘batchtools’ by Lang, Bischel, and Surmann (2017) <[doi:10.21105/joss.00135](https://doi.org/10.21105/joss.00135)>.

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Description

In computationally demanding analysis projects, statisticians and data scientists asynchronously deploy long-running tasks to distributed systems, ranging from traditional clusters to cloud services. The **NNG**-powered **mirai** R package is a sleek and sophisticated scheduler that efficiently processes these intense workloads. The crew package extends **mirai** with a unifying interface for third-party worker launchers. Inspiration also comes from packages **future**, **rrq**, **clustermq**, and **batchtools**.

crew_assert	<i>Crew assertion</i>
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Description

Assert that a condition is true.

Usage

```
crew_assert(value = NULL, ..., message = NULL, envir = parent.frame())
```

Arguments

value	An object or condition.
...	Conditions that use the "." symbol to refer to the object.
message	Optional message to print on error.
envir	Environment to evaluate the condition.

Value

NULL (invisibly). Throws an error if the condition is not true.

See Also

Other utility: [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
crew_assert(1 < 2)
crew_assert("object", !anyNA(.), nzchar(.))
tryCatch(
  crew_assert(2 < 1),
  crew_error = function(condition) message("false")
)
```

crew_class_client R6 *client class*.

Description

R6 class for mirai clients.

Details

See [crew_client\(\)](#).

Active bindings

host See [crew_client\(\)](#).

port See [crew_client\(\)](#).

tls See [crew_client\(\)](#).

serialization See [crew_client\(\)](#).

profile Compute profile of the client.

seconds_interval See [crew_client\(\)](#).

seconds_timeout See [crew_client\(\)](#).

relay Relay object for event-driven programming on a downstream condition variable.

started Whether the client is started.

url Client websocket URL.

Methods

Public methods:

- [crew_class_client\\$new\(\)](#)
- [crew_class_client\\$validate\(\)](#)
- [crew_class_client\\$set_started\(\)](#)
- [crew_class_client\\$start\(\)](#)
- [crew_class_client\\$terminate\(\)](#)
- [crew_class_client\\$status\(\)](#)
- [crew_class_client\\$pids\(\)](#)

Method [new\(\)](#): mirai client constructor.

Usage:

```
crew_class_client$new(  
  host = NULL,  
  port = NULL,  
  tls = NULL,  
  serialization = NULL,  
  profile = NULL,
```

```
    seconds_interval = NULL,  
    seconds_timeout = NULL,  
    relay = NULL  
  )
```

Arguments:

host Argument passed from `crew_client()`.
port Argument passed from `crew_client()`.
tls Argument passed from `crew_client()`.
serialization Argument passed from `crew_client()`.
profile Argument passed from `crew_client()`.
seconds_interval Argument passed from `crew_client()`.
seconds_timeout Argument passed from `crew_client()`.
relay Argument passed from `crew_client()`.

Returns: An R6 object with the client.

Examples:

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {  
  client <- crew_client()  
  client$start()  
  client$log()  
  client$terminate()  
}
```

Method `validate()`: Validate the client.

Usage:

```
crew_class_client$validate()
```

Returns: NULL (invisibly).

Method `set_started()`: Register the client as started.

Usage:

```
crew_class_client$set_started()
```

Details: Exported to implement the sequential controller. Only meant to be called manually inside the client or the sequential controller.

Returns: NULL (invisibly).

Method `start()`: Start listening for workers on the available sockets.

Usage:

```
crew_class_client$start()
```

Returns: NULL (invisibly).

Method `terminate()`: Stop the mirai client and disconnect from the worker websockets.

Usage:

```
crew_class_client$terminate()
```

Returns: NULL (invisibly).

Method `status()`: Get the counters from `mirai::info()`.

Usage:

```
crew_class_client$status()
```

Returns: A named integer vector of task counts (awaiting, executing, completed) as well as the number of worker connections.

Method `pids()`: Deprecated on 2025-08-26 in crew version 1.2.1.9005.

Usage:

```
crew_class_client$pids()
```

Returns: The integer process ID of the current process.

See Also

Other client: [crew_client\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  client$log()
  client$terminate()
}

## -----
## Method `crew_class_client$new`
## -----

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  client$log()
  client$terminate()
}
```

crew_class_controller *Controller class*

Description

R6 class for controllers.

Details

See [crew_controller\(\)](#).

Active bindings

profile Character string, compute profile of the controller.

client Client object.

launcher Launcher object.

tasks A list of `mirai::mirai()` task objects. The list of tasks is dynamically generated from an internal, dictionary, so it is not as fast as a simple lookup.

pushed Number of tasks ever submitted to the mirai compute profile through the controller.

reset_globals See `crew_controller()`. since the controller was started.

reset_packages See `crew_controller()`. since the controller was started.

reset_options See `crew_controller()`. since the controller was started.

garbage_collection See `crew_controller()`. since the controller was started.

crashes_max See `crew_controller()`.

backup See `crew_controller()`.

error Tibble of task results (with one result per row) from the last call to `map(error = "stop")`.

loop later loop if asynchronous auto-scaling is running, NULL otherwise.

queue_resolved Queue of resolved tasks.

queue_backlog Queue of explicitly backlogged tasks.

Methods**Public methods:**

- `crew_class_controller$new()`
- `crew_class_controller$validate()`
- `crew_class_controller$size()`
- `crew_class_controller$empty()`
- `crew_class_controller$nonempty()`
- `crew_class_controller$resolved()`
- `crew_class_controller$unresolved()`
- `crew_class_controller$saturated()`
- `crew_class_controller$start()`
- `crew_class_controller$started()`
- `crew_class_controller$launch()`
- `crew_class_controller$scale()`
- `crew_class_controller$autoscale()`
- `crew_class_controller$descale()`
- `crew_class_controller$crashes()`
- `crew_class_controller$push()`
- `crew_class_controller$synced()`
- `crew_class_controller$walk()`
- `crew_class_controller$map()`
- `crew_class_controller$pop()`

- `crew_class_controller$collect()`
- `crew_class_controller$wait()`
- `crew_class_controller$push_backlog()`
- `crew_class_controller$pop_backlog()`
- `crew_class_controller$summary()`
- `crew_class_controller$cancel()`
- `crew_class_controller$pids()`
- `crew_class_controller$terminate()`

Method `new()`: mirai controller constructor.

Usage:

```
crew_class_controller$new(
  client = NULL,
  launcher = NULL,
  reset_globals = NULL,
  reset_packages = NULL,
  reset_options = NULL,
  garbage_collection = NULL,
  crashes_max = NULL,
  backup = NULL
)
```

Arguments:

`client` Client object. See `crew_controller()`.
`launcher` Launcher object. See `crew_controller()`.
`reset_globals` See `crew_controller()`.
`reset_packages` See `crew_controller()`.
`reset_options` See `crew_controller()`.
`garbage_collection` See `crew_controller()`.
`crashes_max` See `crew_controller()`.
`backup` See `crew_controller()`.

Returns: An R6 controller object.

Examples:

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  launcher <- crew_launcher_local()
  controller <- crew_controller(client = client, launcher = launcher)
  controller$start()
  controller$push(name = "task", command = sqrt(4))
  controller$wait()
  controller$pop()
  controller$terminate()
}
```

Method `validate()`: Validate the controller.

Usage:

crew_class_controller\$validate()

Returns: NULL (invisibly).

Method size(): Number of tasks in the controller.

Usage:

crew_class_controller\$size(controllers = NULL)

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Non-negative integer, number of tasks in the controller.

Method empty(): Check if the controller is empty.

Usage:

crew_class_controller\$empty(controllers = NULL)

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: A controller is empty if it has no `mirai::mirai()` task objects in the controller. There may still be other tasks running on the workers of an empty controller, but those tasks were not submitted with `push()` or `collect()`, and they are not part of the controller task queue.

Returns: TRUE if the controller is empty, FALSE otherwise.

Method nonempty(): Check if the controller is nonempty.

Usage:

crew_class_controller\$nonempty(controllers = NULL)

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: A controller is empty if it has no `mirai::mirai()` task objects in the controller. There may still be other tasks running on the workers of an empty controller, but those tasks were not submitted with `push()` or `collect()`, and they are not part of the controller task queue.

Returns: TRUE if the controller is empty, FALSE otherwise.

Method resolved(): Cumulative number of resolved tasks.

Usage:

crew_class_controller\$resolved(controllers = NULL)

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: `resolved()` is cumulative: it counts all the resolved tasks over the entire lifetime of the controller session.

Returns: Non-negative integer of length 1, number of resolved tasks. The return value is 0 if the condition variable does not exist (i.e. if the client is not running).

Method unresolved(): Number of unresolved tasks.

Usage:

```
crew_class_controller$unresolved(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Non-negative integer of length 1, number of unresolved tasks.

Method saturated(): Check if the controller is saturated.

Usage:

```
crew_class_controller$saturated(
  collect = NULL,
  throttle = NULL,
  controller = NULL
)
```

Arguments:

collect Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

throttle Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: A controller is saturated if the number of uncollected tasks is greater than or equal to the maximum number of workers. You can still push tasks to a saturated controller, but tools that use crew such as targets may choose not to (for performance and user-friendliness).

Returns: TRUE if the controller is saturated, FALSE otherwise.

Method start(): Start the controller if it is not already started.

Usage:

```
crew_class_controller$start(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: Register the mirai client and register worker websockets with the launcher.

Returns: NULL (invisibly).

Method started(): Check whether the controller is started.

Usage:

```
crew_class_controller$started(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: Actually checks whether the client is started.

Returns: TRUE if the controller is started, FALSE otherwise.

Method launch(): Launch one or more workers.

Usage:

```
crew_class_controller$launch(n = 1L, controllers = NULL)
```

Arguments:

n Number of workers to launch.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

Method scale(): Auto-scale workers out to meet the demand of tasks.

Usage:

```
crew_class_controller$scale(throttle = TRUE, controllers = NULL)
```

Arguments:

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time scale() is called. Throttling avoids overburdening the local R process.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: The scale() method launches new workers to run tasks if needed.

Returns: Invisibly returns TRUE if auto-scaling was attempted (throttling can skip it) and there was any relevant auto-scaling activity (new worker launches or worker connection/disconnection events). FALSE otherwise.

Method autoscale(): Run worker auto-scaling in a later loop in polling intervals determined by exponential backoff.

Usage:

```
crew_class_controller$autoscale(  
  loop = later::global_loop(),  
  controllers = NULL  
)
```

Arguments:

loop A later loop to run auto-scaling.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: Call controller\$descale() to terminate the auto-scaling loop.

Returns: NULL (invisibly).

Method descale(): Terminate the auto-scaling loop started by controller\$autoscale().

Usage:

```
crew_class_controller$descale(controllers = NULL)
```

Arguments:

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

Method `crashes()`: Report the number of consecutive crashes of a task.

Usage:

```
crew_class_controller$crashes(name, controllers = NULL)
```

Arguments:

`name` Character string, name of the task to check.

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: See the `crashes_max` argument of `crew_controller()`.

Returns: Non-negative integer, number of consecutive times the task crashed.

Method `push()`: Push a task to the head of the task list.

Usage:

```
crew_class_controller$push(
  command,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(),
  library = NULL,
  seconds_timeout = NULL,
  scale = TRUE,
  throttle = TRUE,
  name = NULL,
  save_command = NULL,
  controller = NULL
)
```

Arguments:

`command` Language object with R code to run.

`data` Named list of local data objects in the evaluation environment.

`globals` Named list of objects to temporarily assign to the global environment for the task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the `reset_globals` argument of `crew_controller_local()`.

`substitute` Logical of length 1, whether to call `base::substitute()` on the supplied value of the `command` argument. If TRUE (default) then `command` is quoted literally as you write it, e.g. `push(command = your_function_call())`. If FALSE, then `crew` assumes `command` is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. `substitute = TRUE` is appropriate for interactive use, whereas `substitute = FALSE` is meant for automated R programs that invoke `crew` controllers.

seed Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the seed argument of `set.seed()` if not NULL. If seed and algorithm are both non-missing in the output of `pop()`, then you can recover the pseudo-random number generator state of the task using `set.seed(seed = seed, kind = algorithm)`. Otherwise, if the algorithm and seed are both NULL (recommended), then the random number generator defaults to the widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

algorithm Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the kind argument of `RNGkind()` if not NULL. If seed and algorithm are both non-missing in the output of `pop()`, then you can recover the pseudo-random number generator state of the task using `set.seed(seed = seed, kind = algorithm)`. Otherwise, if the algorithm and seed are both NULL (recommended), then the random number generator defaults to the widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

packages Character vector of packages to load for the task.

library Library path to load the packages. See the `lib.loc` argument of `require()`.

seconds_timeout Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).

scale Logical, whether to automatically call `scale()` to auto-scale workers to meet the demand of the task load. Also see the `throttle` argument.

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

name Character string, name of the task. If NULL, then a random name is generated automatically. The name of the task must not conflict with the name of another task pushed to the controller. Any previous task with the same name must first be popped before a new task with that name can be pushed.

save_command Deprecated on 2025-01-22 (crew version 0.10.2.9004) and no longer used.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Invisibly return the `mirai` object of the pushed task. This allows you to interact with the task directly, e.g. to create a promise object with `promises::as.promise()`.

Method `synced()`: Check if the controller is synced.

Usage:

```
crew_class_controller$synced(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: A controller is synced if all pushed tasks in the controller show up in the task counts in `mirai::info()`.

Method `walk()`: Apply a single command to multiple inputs, and return control to the user without waiting for any task to complete.

Usage:

```

crew_class_controller$walk(
  command,
  iterate,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(),
  library = NULL,
  seconds_timeout = NULL,
  names = NULL,
  save_command = NULL,
  verbose = interactive(),
  scale = TRUE,
  throttle = TRUE,
  controller = NULL
)

```

Arguments:

command Language object with R code to run.

iterate Named list of vectors or lists to iterate over. For example, to run function calls $f(x = 1, y = "a")$ and $f(x = 2, y = "b")$, set **command** to $f(x, y)$, and set **iterate** to $\text{list}(x = c(1, 2), y = c("a", "b"))$. The individual function calls are evaluated as $f(x = \text{iterate}\$x[[1]], y = \text{iterate}\$y[[1]])$ and $f(x = \text{iterate}\$x[[2]], y = \text{iterate}\$y[[2]])$. All the elements of **iterate** must have the same length. If there are any name conflicts between **iterate** and **data**, **iterate** takes precedence.

data Named list of constant local data objects in the evaluation environment. Objects in this list are treated as single values and are held constant for each iteration of the map.

globals Named list of constant objects to temporarily assign to the global environment for each task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the **reset_globals** argument of [crew_controller_local\(\)](#). Objects in this list are treated as single values and are held constant for each iteration of the map.

substitute Logical of length 1, whether to call `base::substitute()` on the supplied value of the **command** argument. If **TRUE** (default) then **command** is quoted literally as you write it, e.g. `push(command = your_function_call())`. If **FALSE**, then **crew** assumes **command** is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. **substitute = TRUE** is appropriate for interactive use, whereas **substitute = FALSE** is meant for automated R programs that invoke **crew** controllers.

seed Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the **seed** argument of `set.seed()` if not **NULL**. If **algorithm** and **seed** are both **NULL**, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

algorithm Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the **kind** argument of `RNGkind()` if not **NULL**. If **algorithm** and **seed** are both **NULL**, then the random number generator defaults to the rec-

commended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

`packages` Character vector of packages to load for the task.

`library` Library path to load the packages. See the `lib.loc` argument of `require()`.

`seconds_timeout` Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).

`names` Optional character of length 1, name of the element of `iterate` with names for the tasks. If `names` is supplied, then `iterate[[names]]` must be a character vector.

`save_command` Deprecated on 2025-01-22 (crew version 0.10.2.9004). The command is always saved now.

`verbose` Logical of length 1, whether to print to a progress bar when pushing tasks.

`scale` Logical, whether to automatically scale workers to meet demand. See also the `throttle` argument.

`throttle` TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

`controller` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: In contrast to `walk()`, `map()` blocks the local R session and waits for all tasks to complete.

Returns: Invisibly returns a list of `mirai` task objects for the newly created tasks. The order of tasks in the list matches the order of data in the `iterate` argument.

Method `map()`: Apply a single command to multiple inputs, wait for all tasks to complete, and return the results of all tasks.

Usage:

```
crew_class_controller$map(
  command,
  iterate,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(0),
  library = NULL,
  seconds_interval = NULL,
  seconds_timeout = NULL,
  names = NULL,
  save_command = NULL,
  error = "stop",
  warnings = TRUE,
  verbose = interactive(),
  scale = TRUE,
  throttle = TRUE,
  controller = NULL
)
```

Arguments:

command Language object with R code to run.

iterate Named list of vectors or lists to iterate over. For example, to run function calls $f(x = 1, y = "a")$ and $f(x = 2, y = "b")$, set **command** to $f(x, y)$, and set **iterate** to $\text{list}(x = c(1, 2), y = c("a", "b"))$. The individual function calls are evaluated as $f(x = \text{iterate}\$x[[1]], y = \text{iterate}\$y[[1]])$ and $f(x = \text{iterate}\$x[[2]], y = \text{iterate}\$y[[2]])$. All the elements of **iterate** must have the same length. If there are any name conflicts between **iterate** and **data**, **iterate** takes precedence.

data Named list of constant local data objects in the evaluation environment. Objects in this list are treated as single values and are held constant for each iteration of the map.

globals Named list of constant objects to temporarily assign to the global environment for each task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the `reset_globals` argument of `crew_controller_local()`. Objects in this list are treated as single values and are held constant for each iteration of the map.

substitute Logical of length 1, whether to call `base::substitute()` on the supplied value of the **command** argument. If **TRUE** (default) then **command** is quoted literally as you write it, e.g. `push(command = your_function_call())`. If **FALSE**, then **crew** assumes **command** is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. **substitute = TRUE** is appropriate for interactive use, whereas **substitute = FALSE** is meant for automated R programs that invoke **crew** controllers.

seed Integer of length 1 with the pseudo-random number generator **seed** to set for the evaluation of the task. Passed to the `seed` argument of `set.seed()` if not **NULL**. If **algorithm** and **seed** are both **NULL**, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

algorithm Integer of length 1 with the pseudo-random number generator **algorithm** to set for the evaluation of the task. Passed to the `kind` argument of `RNGkind()` if not **NULL**. If **algorithm** and **seed** are both **NULL**, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

packages Character vector of packages to load for the task.

library Library path to load the packages. See the `lib.loc` argument of `require()`.

seconds_interval Deprecated on 2025-01-17 (crew version 0.10.2.9003). Instead, the `seconds_interval` argument passed to `crew_controller_group()` is used as `seconds_max` in a `crew_throttle()` object which orchestrates exponential backoff.

seconds_timeout Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).

names Optional character string, name of the element of **iterate** with names for the tasks. If **names** is supplied, then `iterate[[names]]` must be a character vector.

save_command Deprecated on 2025-01-22 (crew version 0.10.2.9004). The **command** is always saved now.

error Character of length 1, choice of action if a task was not successful. Possible values:

- **"stop"**: throw an error in the main R session instead of returning a value. In case of an error, the results from the last errored `map()` are in the `error` field of the controller, e.g. `controller_object$error`. To reduce memory consumption, set `controller_object$error <- NULL` after you are finished troubleshooting.

- "warn": throw a warning. This allows the return value with all the error messages and tracebacks to be generated.
- "silent": do nothing special. NOTE: the only kinds of errors considered here are errors at the R level. A crashed tasks will return a status of "crash" in the output and not trigger an error in map() unless crashes_max is reached.

warnings Logical of length 1, whether to throw a warning in the interactive session if at least one task encounters an error.

verbose Logical of length 1, whether to print to a progress bar as tasks resolve.

scale Logical, whether to automatically scale workers to meet demand. See also the throttle argument.

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time scale() is called. Throttling avoids overburdening the local R process.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: map() cannot be used unless all prior tasks are completed and popped. You may need to wait and then pop them manually. Alternatively, you can start over: either call terminate() on the current controller object to reset it, or create a new controller object entirely.

Returns: A tibble of results and metadata: one row per task and columns corresponding to the output of pop().

Method pop(): Pop a completed task from the results data frame.

Usage:

```
crew_class_controller$pop(
  scale = TRUE,
  collect = NULL,
  throttle = TRUE,
  error = NULL,
  controllers = NULL
)
```

Arguments:

scale Logical of length 1, whether to automatically call scale() to auto-scale workers to meet the demand of the task load. Scaling up on pop() may be important for transient or nearly transient workers that tend to drop off quickly after doing little work. See also the throttle argument.

collect Deprecated in version 0.5.0.9003 (2023-10-02).

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time scale() is called. Throttling avoids overburdening the local R process.

error NULL or character of length 1, choice of action if the popped task threw an error. Possible values:

- "stop": throw an error in the main R session instead of returning a value.
- "warn": throw a warning.
- NULL or "silent": do not react to errors. NOTE: the only kinds of errors considered here are errors at the R level. A crashed tasks will return a status of "crash" in the output and not trigger an error in pop() unless crashes_max is reached.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: If not task is currently completed, pop() will attempt to auto-scale workers as needed.

Returns: If there is no task to collect, return NULL. Otherwise, return a one-row tibble with the following columns.

- name: the task name.
- command: a character string with the R command.
- result: a list containing the return value of the R command. NA if the task failed.
- status: a character string. "success" if the task succeeded, "cancel" if the task was canceled with the cancel() controller method, "crash" if the worker running the task exited before it could complete the task, or "error" for any other kind of error.
- error: the first 2048 characters of the error message if the task status is not "success", NA otherwise. Messages for crashes and cancellations are captured here alongside ordinary R-level errors.
- code: an integer code denoting the specific exit status: 0 for successful tasks, -1 for tasks with an error in the R command of the task, and another positive integer with an NNG status code if there is an error at the NNG/nanonext level. nanonext::nng_error() can interpret these codes.
- trace: the first 2048 characters of the text of the traceback if the task threw an error, NA otherwise.
- warnings: the first 2048 characters. of the text of warning messages that the task may have generated, NA otherwise.
- seconds: number of seconds that the task ran.
- seed: the single integer originally supplied to push(), NA otherwise. The pseudo-random number generator state just prior to the task can be restored using set.seed(seed = seed, kind = algorithm), where seed and algorithm are part of this output.
- algorithm: name of the pseudo-random number generator algorithm originally supplied to push(), NA otherwise. The pseudo-random number generator state just prior to the task can be restored using set.seed(seed = seed, kind = algorithm), where seed and algorithm are part of this output.
- controller: name of the crew controller where the task ran.
- worker: name of the crew worker that ran the task.

Method collect(): Pop all available task results and return them in a tidy tibble.

Usage:

```
crew_class_controller$collect(
  scale = TRUE,
  throttle = TRUE,
  error = NULL,
  controllers = NULL
)
```

Arguments:

scale Logical of length 1, whether to automatically call scale() to auto-scale workers to meet the demand of the task load.

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

error NULL or character of length 1, choice of action if the popped task threw an error. Possible values: * "stop": throw an error in the main R session instead of returning a value. * "warn": throw a warning. * NULL or "silent": do not react to errors. NOTE: the only kinds of errors considered here are errors at the R level. A crashed tasks will return a status of "crash" in the output and not trigger an error in `collect()` unless `crashes_max` is reached.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: A tibble of results and metadata of all resolved tasks, with one row per task. Returns NULL if there are no tasks to collect. See `pop()` for details on the columns of the returned tibble.

Method `wait()`: Wait for tasks.

Usage:

```
crew_class_controller$wait(
  mode = "all",
  seconds_interval = NULL,
  seconds_timeout = Inf,
  scale = TRUE,
  throttle = TRUE,
  controllers = NULL
)
```

Arguments:

mode Character string, name of the waiting condition. `wait(mode = "all")` waits until all tasks in the `mirai` compute profile resolve, and `wait(mode = "one")` waits until at least one task is available to `push()` or `collect()` from the controller. The former still works if the controller is not the only means of submitting tasks to the compute profile, whereas the latter assumes only the controller submits tasks.

seconds_interval Deprecated on 2025-01-17 (crew version 0.10.2.9003). Instead, the `seconds_interval` argument passed to `crew_controller_group()` is used as `seconds_max` in a `crew_throttle()` object which orchestrates exponential backoff.

seconds_timeout Timeout length in seconds waiting for tasks.

scale Logical, whether to automatically call `scale()` to auto-scale workers to meet the demand of the task load. See also the `throttle` argument.

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: The `wait()` method blocks the calling R session and (optionally) auto-scales workers until the condition in the `mode` argument is met. NOTE: `wait()` may register a task as resolved a split second before the task handle is ready for `pop()` or `collect()`. If `wait()` returns but `pop()` returns NULL, simply retry `pop()` a short time later.

Returns: A logical of length 1, invisibly. `wait(mode = "all")` returns TRUE if all tasks in the mirai compute profile have resolved (FALSE otherwise). `wait(mode = "one")` returns TRUE if the controller is ready to pop or collect at least one resolved task (FALSE otherwise). `wait(mode = "one")` assumes all tasks were submitted through the controller and not by other means.

Method `push_backlog()`: Push the name of a task to the backlog.

Usage:

```
crew_class_controller$push_backlog(name, controller = NULL)
```

Arguments:

`name` Character of length 1 with the task name to push to the backlog.

`controller` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: `pop_backlog()` pops the tasks that can be pushed without saturating the controller.

Returns: NULL (invisibly).

Method `pop_backlog()`: Pop the task names from the head of the backlog which can be pushed without saturating the controller.

Usage:

```
crew_class_controller$pop_backlog(controllers = NULL)
```

Arguments:

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Character vector of task names which can be pushed to the controller without saturating it. If the controller is saturated, `character(0L)` is returned.

Method `summary()`: Summarize the collected tasks of the controller.

Usage:

```
crew_class_controller$summary(controllers = NULL)
```

Arguments:

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: A data frame of cumulative summary statistics on the tasks collected through `pop()` and `collect()`. It has one row and the following columns:

- `controller`: name of the controller.
- `seconds`: total number of runtime in seconds.
- `tasks`: total number of tasks collected.
- `success`: total number of collected tasks that did not crash or error.
- `error`: total number of tasks with errors, either in the R code of the task or an NNG-level error that is not a cancellation or crash.
- `crash`: total number of crashed tasks (where the worker exited unexpectedly while it was running the task).
- `cancel`: total number of tasks interrupted with the `cancel()` controller method.
- `warning`: total number of tasks with one or more warnings.

Method `cancel()`: Cancel one or more tasks.

Usage:

```
crew_class_controller$cancel(names = character(0L), all = FALSE)
```

Arguments:

`names` Character vector of names of tasks to cancel. Those names must have been manually supplied by `push()`.

`all` TRUE to cancel all tasks, FALSE otherwise. `all = TRUE` supersedes the `names` argument.

Returns: NULL (invisibly).

Method `pids()`: Deprecated on 2025-08-26 in crew version 1.2.1.9005.

Usage:

```
crew_class_controller$pids(controllers = NULL)
```

Arguments:

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: The integer process ID of the current process.

Method `terminate()`: Terminate the workers and the mirai client.

Usage:

```
crew_class_controller$terminate(controllers = NULL)
```

Arguments:

`controllers` Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

See Also

Other controller: [crew_controller\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  launcher <- crew_launcher_local()
  controller <- crew_controller(client = client, launcher = launcher)
  controller$start()
  controller$push(name = "task", command = sqrt(4))
  controller$wait()
  controller$pop()
  controller$terminate()
}
```

```
## -----
## Method `crew_class_controller$new`
## -----
```

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  launcher <- crew_launcher_local()
  controller <- crew_controller(client = client, launcher = launcher)
  controller$start()
  controller$push(name = "task", command = sqrt(4))
  controller$wait()
  controller$pop()
  controller$terminate()
}
```

crew_class_controller_group

Controller group class

Description

R6 class for controller groups.

Details

See [crew_controller_group\(\)](#).

Active bindings

controllers List of R6 controller objects.

relay Relay object for event-driven programming on a downstream condition variable.

Methods

Public methods:

- [crew_class_controller_group\\$new\(\)](#)
- [crew_class_controller_group\\$validate\(\)](#)
- [crew_class_controller_group\\$size\(\)](#)
- [crew_class_controller_group\\$empty\(\)](#)
- [crew_class_controller_group\\$nonempty\(\)](#)
- [crew_class_controller_group\\$resolved\(\)](#)
- [crew_class_controller_group\\$unresolved\(\)](#)
- [crew_class_controller_group\\$saturated\(\)](#)
- [crew_class_controller_group\\$start\(\)](#)
- [crew_class_controller_group\\$started\(\)](#)
- [crew_class_controller_group\\$launch\(\)](#)
- [crew_class_controller_group\\$scale\(\)](#)
- [crew_class_controller_group\\$autoscale\(\)](#)
- [crew_class_controller_group\\$descale\(\)](#)

- crew_class_controller_group\$crashes()
- crew_class_controller_group\$push()
- crew_class_controller_group\$synced()
- crew_class_controller_group\$walk()
- crew_class_controller_group\$map()
- crew_class_controller_group\$pop()
- crew_class_controller_group\$collect()
- crew_class_controller_group\$wait()
- crew_class_controller_group\$push_backlog()
- crew_class_controller_group\$pop_backlog()
- crew_class_controller_group\$summary()
- crew_class_controller_group\$pids()
- crew_class_controller_group\$terminate()

Method new(): Multi-controller constructor.

Usage:

```
crew_class_controller_group$new(controllers = NULL, relay = NULL)
```

Arguments:

controllers List of R6 controller objects.

relay Relay object for event-driven programming on a downstream condition variable.

Returns: An R6 object with the controller group object.

Examples:

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  persistent <- crew_controller_local(name = "persistent")
  transient <- crew_controller_local(
    name = "transient",
    tasks_max = 1L
  )
  group <- crew_controller_group(persistent, transient)
  group$start()
  group$push(name = "task", command = sqrt(4), controller = "transient")
  group$wait()
  group$pop()
  group$terminate()
}
```

Method validate(): Validate the client.

Usage:

```
crew_class_controller_group$validate()
```

Returns: NULL (invisibly).

Method size(): Number of tasks in the selected controllers.

Usage:

```
crew_class_controller_group$size(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: Non-negative integer, number of tasks in the controller.

Method empty(): See if the controllers are empty.

Usage:

```
crew_class_controller_group$empty(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: A controller is empty if it has no running tasks or completed tasks waiting to be retrieved with push().

Returns: TRUE if all the selected controllers are empty, FALSE otherwise.

Method nonempty(): Check if the controller group is nonempty.

Usage:

```
crew_class_controller_group$nonempty(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: A controller is empty if it has no running tasks or completed tasks waiting to be retrieved with push().

Returns: TRUE if the controller is empty, FALSE otherwise.

Method resolved(): Number of resolved mirai() tasks.

Usage:

```
crew_class_controller_group$resolved(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: resolved() is cumulative: it counts all the resolved tasks over the entire lifetime of the controller session.

Returns: Non-negative integer of length 1, number of resolved mirai() tasks. The return value is 0 if the condition variable does not exist (i.e. if the client is not running).

Method unresolved(): Number of unresolved mirai() tasks.

Usage:

```
crew_class_controller_group$unresolved(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: Non-negative integer of length 1, number of unresolved mirai() tasks.

Method saturated(): Check if a controller is saturated.

Usage:

```
crew_class_controller_group$saturated(
  collect = NULL,
  throttle = NULL,
  controller = NULL
)
```

Arguments:

collect Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

throttle Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

controller Character vector of length 1 with the controller name. Set to NULL to select the default controller that `push()` would choose.

Details: A controller is saturated if the number of uncollected tasks is greater than or equal to the maximum number of workers. You can still push tasks to a saturated controller, but tools that use crew such as targets may choose not to (for performance and user-friendliness).

Returns: TRUE if all the selected controllers are saturated, FALSE otherwise.

Method `start()`: Start one or more controllers.

Usage:

```
crew_class_controller_group$start(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: NULL (invisibly).

Method `started()`: Check whether all the given controllers are started.

Usage:

```
crew_class_controller_group$started(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: Actually checks whether all the given clients are started.

Returns: TRUE if the controllers are started, FALSE if any are not.

Method `launch()`: Launch one or more workers on one or more controllers.

Usage:

```
crew_class_controller_group$launch(n = 1L, controllers = NULL)
```

Arguments:

n Number of workers to launch in each controller selected.

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: NULL (invisibly).

Method `scale()`: Automatically scale up the number of workers if needed in one or more controller objects.

Usage:

```
crew_class_controller_group$scale(throttle = TRUE, controllers = NULL)
```

Arguments:

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: See the `scale()` method in individual controller classes.

Returns: Invisibly returns TRUE if there was any relevant auto-scaling activity (new worker launches or worker connection/disconnection events) (FALSE otherwise).

Method `autoscale()`: Run worker auto-scaling in a later loop.

Usage:

```
crew_class_controller_group$autoscale(
  loop = later::current_loop(),
  controllers = NULL
)
```

Arguments:

loop A later loop to run auto-scaling.

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: NULL (invisibly).

Method `descale()`: Terminate the auto-scaling loop started by `controller$autoscale()`.

Usage:

```
crew_class_controller_group$descale(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Returns: NULL (invisibly).

Method `crashes()`: Report the number of consecutive crashes of a task, summed over all selected controllers in the group.

Usage:

```
crew_class_controller_group$crashes(name, controllers = NULL)
```

Arguments:

name Character string, name of the task to check.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: See the `crashes_max` argument of `crew_controller()`.

Returns: Number of consecutive crashes of the named task, summed over all the controllers in the group.

Method `push()`: Push a task to the head of the task list.

Usage:

```

crew_class_controller_group$push(
  command,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(0),
  library = NULL,
  seconds_timeout = NULL,
  scale = TRUE,
  throttle = TRUE,
  name = NULL,
  save_command = NULL,
  controller = NULL
)

```

Arguments:

`command` Language object with R code to run.

`data` Named list of local data objects in the evaluation environment.

`globals` Named list of objects to temporarily assign to the global environment for the task. See the `reset_globals` argument of `crew_controller_local()`.

`substitute` Logical of length 1, whether to call `base::substitute()` on the supplied value of the `command` argument. If `TRUE` (default) then `command` is quoted literally as you write it, e.g. `push(command = your_function_call())`. If `FALSE`, then `crew` assumes `command` is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. `substitute = TRUE` is appropriate for interactive use, whereas `substitute = FALSE` is meant for automated R programs that invoke `crew` controllers.

`seed` Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the `seed` argument of `set.seed()` if not `NULL`. If `algorithm` and `seed` are both `NULL`, then the random number generator defaults to the widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

`algorithm` Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the `kind` argument of `RNGkind()` if not `NULL`. If `algorithm` and `seed` are both `NULL`, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

`packages` Character vector of packages to load for the task.

`library` Library path to load the packages. See the `lib.loc` argument of `require()`.

`seconds_timeout` Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).

`scale` Logical, whether to automatically scale workers to meet demand. See the `scale` argument of the `push()` method of ordinary single controllers.

`throttle` `TRUE` to skip auto-scaling if it already happened within the last polling interval. `FALSE` to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

name Character string, name of the task. If NULL, a random name is automatically generated.

The task name must not conflict with an existing task in the controller where it is submitted.

To reuse the name, wait for the existing task to finish, then either `pop()` or `collect()` it to remove it from its controller.

save_command Deprecated on 2025-01-22 (crew version 0.10.2.9004).

controller Character of length 1, name of the controller to submit the task. If NULL, the controller defaults to the first controller in the list.

Returns: Invisibly return the `mirai` object of the pushed task. This allows you to interact with the task directly, e.g. to create a promise object with `promises::as.promise()`.

Method `synced()`: Check if all controllers are synced.

Usage:

```
crew_class_controller_group$synced(controllers = NULL)
```

Arguments:

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: A controller is synced if all pushed tasks in the controller show up in the task counts in `mirai::info()`.

Method `walk()`: Apply a single command to multiple inputs, and return control to the user without waiting for any task to complete.

Usage:

```
crew_class_controller_group$walk(
  command,
  iterate,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(0),
  library = NULL,
  seconds_timeout = NULL,
  names = NULL,
  save_command = NULL,
  verbose = interactive(),
  scale = TRUE,
  throttle = TRUE,
  controller = NULL
)
```

Arguments:

command Language object with R code to run.

iterate Named list of vectors or lists to iterate over. For example, to run function calls `f(x = 1, y = "a")` and `f(x = 2, y = "b")`, set `command` to `f(x, y)`, and set `iterate` to `list(x = c(1, 2), y = c("a", "b"))`. The individual function calls are evaluated as `f(x = iterate$x[[1]], y = iterate$y[[1]])` and `f(x = iterate$x[[2]], y = iterate$y[[2]])`. All the elements of `iterate` must have the same length. If there are any name conflicts between `iterate` and `data`, `iterate` takes precedence.

- data** Named list of constant local data objects in the evaluation environment. Objects in this list are treated as single values and are held constant for each iteration of the map.
- globals** Named list of constant objects to temporarily assign to the global environment for each task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the `reset_globals` argument of `crew_controller_local()`. Objects in this list are treated as single values and are held constant for each iteration of the map.
- substitute** Logical of length 1, whether to call `base::substitute()` on the supplied value of the command argument. If TRUE (default) then command is quoted literally as you write it, e.g. `push(command = your_function_call())`. If FALSE, then crew assumes command is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. `substitute = TRUE` is appropriate for interactive use, whereas `substitute = FALSE` is meant for automated R programs that invoke crew controllers.
- seed** Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the `seed` argument of `set.seed()` if not NULL. If `algorithm` and `seed` are both NULL, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.
- algorithm** Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the `kind` argument of `RNGkind()` if not NULL. If `algorithm` and `seed` are both NULL, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.
- packages** Character vector of packages to load for the task.
- library** Library path to load the packages. See the `lib.loc` argument of `require()`.
- seconds_timeout** Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).
- names** Optional character of length 1, name of the element of `iterate` with names for the tasks. If `names` is supplied, then `iterate[[names]]` must be a character vector.
- save_command** Deprecated on 2025-01-22 (crew version 0.10.2.9004).
- verbose** Logical of length 1, whether to print to a progress bar when pushing tasks.
- scale** Logical, whether to automatically scale workers to meet demand. See also the `throttle` argument.
- throttle** TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.
- controller** Character of length 1, name of the controller to submit the tasks. If NULL, the controller defaults to the first controller in the list.

Details: In contrast to `walk()`, `map()` blocks the local R session and waits for all tasks to complete.

Returns: Invisibly returns a list of `mirai` task objects for the newly created tasks. The order of tasks in the list matches the order of `data` in the `iterate` argument.

Method `map()`: Apply a single command to multiple inputs.

Usage:

```

crew_class_controller_group$map(
  command,
  iterate,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(0),
  library = NULL,
  seconds_interval = NULL,
  seconds_timeout = NULL,
  names = NULL,
  save_command = NULL,
  error = "stop",
  warnings = TRUE,
  verbose = interactive(),
  scale = TRUE,
  throttle = TRUE,
  controller = NULL
)

```

Arguments:

command Language object with R code to run.

iterate Named list of vectors or lists to iterate over. For example, to run function calls $f(x=1, y="a")$ and $f(x=2, y="b")$, set **command** to $f(x, y)$, and set **iterate** to $\text{list}(x = c(1, 2), y = c("a", "b"))$. The individual function calls are evaluated as $f(x = \text{iterate}\$x[[1]], y = \text{iterate}\$y[[1]])$ and $f(x = \text{iterate}\$x[[2]], y = \text{iterate}\$y[[2]])$. All the elements of **iterate** must have the same length. If there are any name conflicts between **iterate** and **data**, **iterate** takes precedence.

data Named list of constant local data objects in the evaluation environment. Objects in this list are treated as single values and are held constant for each iteration of the map.

globals Named list of constant objects to temporarily assign to the global environment for each task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the **reset_globals** argument of [crew_controller_local\(\)](#). Objects in this list are treated as single values and are held constant for each iteration of the map.

substitute Logical of length 1, whether to call `base::substitute()` on the supplied value of the **command** argument. If **TRUE** (default) then **command** is quoted literally as you write it, e.g. `push(command = your_function_call())`. If **FALSE**, then **crew** assumes **command** is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. **substitute = TRUE** is appropriate for interactive use, whereas **substitute = FALSE** is meant for automated R programs that invoke **crew** controllers.

seed Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the **seed** argument of `set.seed()` if not **NULL**. If **algorithm** and **seed** are both **NULL**, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

algorithm Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the `kind` argument of `RNGkind()` if not `NULL`. If `algorithm` and `seed` are both `NULL`, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by `mirai::nextstream()`. See `vignette("parallel", package = "parallel")` for details.

packages Character vector of packages to load for the task.

library Library path to load the packages. See the `lib.loc` argument of `require()`.

seconds_interval Deprecated on 2025-01-17 (crew version 0.10.2.9003). Instead, the `seconds_interval` argument passed to `crew_controller_group()` is used as `seconds_max` in a `crew_throttle()` object which orchestrates exponential backoff.

seconds_timeout Optional task timeout passed to the `.timeout` argument of `mirai::mirai()` (after converting to milliseconds).

names Optional character of length 1, name of the element of `iterate` with names for the tasks. If `names` is supplied, then `iterate[[names]]` must be a character vector.

save_command Deprecated on 2025-01-22 (crew version 0.10.2.9004).

error Character vector of length 1, choice of action if a task has an error. Possible values:

- "stop": throw an error in the main R session instead of returning a value. In case of an error, the results from the last errored `map()` are in the `error` field of the controller, e.g. `controller_object$error`. To reduce memory consumption, set `controller_object$error <- NULL` after you are finished troubleshooting.
- "warn": throw a warning. This allows the return value with all the error messages and tracebacks to be generated.
- "silent": do nothing special.

warnings Logical of length 1, whether to throw a warning in the interactive session if at least one task encounters an error.

verbose Logical of length 1, whether to print progress messages.

scale Logical, whether to automatically scale workers to meet demand. See also the `throttle` argument.

throttle `TRUE` to skip auto-scaling if it already happened within the last polling interval. `FALSE` to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

controller Character of length 1, name of the controller to submit the tasks. If `NULL`, the controller defaults to the first controller in the list.

Details: The idea comes from functional programming: for example, the `map()` function from the `purrr` package.

Returns: A tibble of results and metadata: one row per task and columns corresponding to the output of `pop()`.

Method `pop()`: Pop a completed task from the results data frame.

Usage:

```
crew_class_controller_group$pop(
  scale = TRUE,
  collect = NULL,
  throttle = TRUE,
  error = NULL,
```

```

  controllers = NULL
)

```

Arguments:

`scale` Logical, whether to automatically scale workers to meet demand. See the `scale` argument of the `pop()` method of ordinary single controllers.

`collect` Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

`throttle` TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

`error` NULL or character of length 1, choice of action if the popped task threw an error. Possible values:

- "stop": throw an error in the main R session instead of returning a value.
- "warn": throw a warning.
- NULL or "silent": do not react to errors.

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: If there is no task to collect, return NULL. Otherwise, return a one-row tibble with the same columns as `pop()` for ordinary controllers.

Method `collect()`: Pop all available task results and return them in a tidy tibble.

Usage:

```

crew_class_controller_group$collect(
  scale = TRUE,
  throttle = TRUE,
  error = NULL,
  controllers = NULL
)

```

Arguments:

`scale` Logical of length 1, whether to automatically call `scale()` to auto-scale workers to meet the demand of the task load.

`throttle` TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

`error` NULL or character of length 1, choice of action if the popped task threw an error. Possible values:

- "stop": throw an error in the main R session instead of returning a value.
- "warn": throw a warning.
- NULL or "silent": do not react to errors.

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: A tibble of results and metadata of all resolved tasks, with one row per task. Returns NULL if there are no available results.

Method `wait()`: Wait for tasks.

Usage:

```

crew_class_controller_group$wait(
  mode = "all",
  seconds_interval = NULL,
  seconds_timeout = Inf,
  scale = TRUE,
  throttle = TRUE,
  controllers = NULL
)

```

Arguments:

mode Character string, name of the waiting condition. `wait(mode = "all")` waits until all tasks in the mirai compute profile resolve, and `wait(mode = "one")` waits until at least one task is available to `push()` or `collect()` from the controller. The former still works if the controller is not the only means of submitting tasks to the compute profile, whereas the latter assumes only the controller submits tasks.

seconds_interval Deprecated on 2025-01-17 (crew version 0.10.2.9003). Instead, the `seconds_interval` argument passed to `crew_controller_group()` is used as `seconds_max` in a `crew_throttle()` object which orchestrates exponential backoff.

seconds_timeout Timeout length in seconds waiting for results to become available.

scale Logical of length 1, whether to call `scale_later()` on each selected controller to schedule auto-scaling. See the `scale` argument of the `wait()` method of ordinary single controllers.

throttle TRUE to skip auto-scaling if it already happened within the last polling interval. FALSE to auto-scale every time `scale()` is called. Throttling avoids overburdening the local R process.

controllers Character vector of controller names. Set to NULL to select all controllers.

Details: The `wait()` method blocks the calling R session until the condition in the `mode` argument is met. During the wait, `wait()` iteratively auto-scales the workers.

Returns: A logical of length 1, invisibly. `wait(mode = "all")` returns TRUE if all tasks in the mirai compute profile have resolved (FALSE otherwise). `wait(mode = "one")` returns TRUE if the controller is ready to pop or collect at least one resolved task (FALSE otherwise). `wait(mode = "one")` assumes all tasks were submitted through the controller and not by other means.

Method `push_backlog()`: Push the name of a task to the backlog.

Usage:

```
crew_class_controller_group$push_backlog(name, controller = NULL)
```

Arguments:

name Character of length 1 with the task name to push to the backlog.

controller Character vector of length 1 with the controller name. Set to NULL to select the default controller that `push_backlog()` would choose.

Details: `pop_backlog()` pops the tasks that can be pushed without saturating the controller.

Returns: NULL (invisibly).

Method `pop_backlog()`: Pop the task names from the head of the backlog which can be pushed without saturating the controller.

Usage:

```
crew_class_controller_group$pop_backlog(controllers = NULL)
```

Arguments:

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: Character vector of task names which can be pushed to the controller without saturating it. If the controller is saturated, `character(0L)` is returned.

Method `summary()`: Summarize the workers of one or more controllers.

Usage:

```
crew_class_controller_group$summary(controllers = NULL)
```

Arguments:

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: A data frame of aggregated worker summary statistics of all the selected controllers. It has one row per worker, and the rows are grouped by controller. See the documentation of the `summary()` method of the controller class for specific information about the columns in the output.

Method `pids()`: Deprecated on 2025-08-26 in crew version 1.2.1.9005.

Usage:

```
crew_class_controller_group$pids(controllers = NULL)
```

Arguments:

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: The integer process ID of the current process.

Method `terminate()`: Terminate the workers and disconnect the client for one or more controllers.

Usage:

```
crew_class_controller_group$terminate(controllers = NULL)
```

Arguments:

`controllers` Character vector of controller names. Set to NULL to select all controllers.

Returns: NULL (invisibly).

See Also

Other controller_group: [crew_controller_group\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  persistent <- crew_controller_local(name = "persistent")
  transient <- crew_controller_local(
    name = "transient",
    tasks_max = 1L
  )
  group <- crew_controller_group(persistent, transient)
  group$start()
```

```

group$push(name = "task", command = sqrt(4), controller = "transient")
group$wait()
group$pop()
group$terminate()
}

## -----
## Method `crew_class_controller_group$new`
## -----

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  persistent <- crew_controller_local(name = "persistent")
  transient <- crew_controller_local(
    name = "transient",
    tasks_max = 1L
  )
  group <- crew_controller_group(persistent, transient)
  group$start()
  group$push(name = "task", command = sqrt(4), controller = "transient")
  group$wait()
  group$pop()
  group$terminate()
}

```

```

crew_class_controller_sequential
  Sequential controller class

```

Description

R6 class for sequential controllers.

Details

See [crew_controller_sequential\(\)](#).

Super class

`crew::crew_class_controller` -> `crew_class_controller_sequential`

Methods**Public methods:**

- `crew_class_controller_sequential$resolved()`
- `crew_class_controller_sequential$unresolved()`
- `crew_class_controller_sequential$saturated()`
- `crew_class_controller_sequential$start()`
- `crew_class_controller_sequential$launch()`

- crew_class_controller_sequential\$scale()
- crew_class_controller_sequential\$autoscale()
- crew_class_controller_sequential\$descale()
- crew_class_controller_sequential\$push()
- crew_class_controller_sequential\$wait()
- crew_class_controller_sequential\$push_backlog()
- crew_class_controller_sequential\$pop_backlog()
- crew_class_controller_sequential\$cancel()
- crew_class_controller_sequential\$terminate()

Method resolved(): Number of resolved tasks.

Usage:

```
crew_class_controller_sequential$resolved(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: resolved() is cumulative: it counts all the resolved tasks over the entire lifetime of the controller session. For the sequential controller, tasks are resolved as soon as they are pushed.

Returns: Non-negative integer of length 1, number of resolved tasks. The return value is 0 if the condition variable does not exist (i.e. if the client is not running).

Method unresolved(): Number of unresolved tasks.

Usage:

```
crew_class_controller_sequential$unresolved(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Returns 0 always because the sequential controller resolves tasks as soon as they are pushed.

Method saturated(): Check if the controller is saturated.

Usage:

```
crew_class_controller_sequential$saturated(
  collect = NULL,
  throttle = NULL,
  controller = NULL
)
```

Arguments:

collect Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

throttle Deprecated in version 0.5.0.9003 (2023-10-02). Not used.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Always returns FALSE for the sequential controller because tasks run immediately on the local process and there are no workers.

Method start(): Start the controller if it is not already started.

Usage:

```
crew_class_controller_sequential$start(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Details: For the sequential controller, there is nothing to do except register the client as started.

Returns: NULL (invisibly).

Method launch(): Does nothing for the sequential controller.

Usage:

```
crew_class_controller_sequential$launch(n = 1L, controllers = NULL)
```

Arguments:

n Number of workers to launch.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

Method scale(): Does nothing for the sequential controller.

Usage:

```
crew_class_controller_sequential$scale(throttle = TRUE, controllers = NULL)
```

Arguments:

throttle Not applicable to the sequential controller.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Invisibly returns FALSE.

Method autoscale(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$autoscale(loop = NULL, controllers = NULL)
```

Arguments:

loop Not used by sequential controllers. Included to ensure the signature is compatible with the analogous method of controller groups.

controllers Not used by sequential controllers. Included to ensure the signature is compatible with the analogous method of controller groups.

Method descale(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$descale(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

Method push(): Push a task to the head of the task list.

Usage:

```
crew_class_controller_sequential$push(
  command,
  data = list(),
  globals = list(),
  substitute = TRUE,
  seed = NULL,
  algorithm = NULL,
  packages = character(0),
  library = NULL,
  seconds_timeout = NULL,
  scale = TRUE,
  throttle = TRUE,
  name = NULL,
  save_command = NULL,
  controller = NULL
)
```

Arguments:

command Language object with R code to run.

data Named list of local data objects in the evaluation environment.

globals Named list of objects to temporarily assign to the global environment for the task. This list should include any functions you previously defined in the global environment which are required to run tasks. See the `reset_globals` argument of `crew_controller_local()`.

substitute Logical of length 1, whether to call `base::substitute()` on the supplied value of the command argument. If TRUE (default) then command is quoted literally as you write it, e.g. `push(command = your_function_call())`. If FALSE, then crew assumes command is a language object and you are passing its value, e.g. `push(command = quote(your_function_call()))`. `substitute = TRUE` is appropriate for interactive use, whereas `substitute = FALSE` is meant for automated R programs that invoke crew controllers.

seed Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the `seed` argument of `set.seed()` if not NULL. If `algorithm` and `seed` are both NULL for the sequential controller, then the random number generator defaults to the current RNG of the local R session where the sequential controller lives.

algorithm Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the `kind` argument of `RNGkind()` if not NULL. If `algorithm` and `seed` are both NULL for the sequential controller, then the random number generator defaults to the current RNG of the local R session where the sequential controller lives.

packages Character vector of packages to load for the task.

library Library path to load the packages. See the `lib.loc` argument of `require()`.

seconds_timeout Not used in the sequential controller..

scale Not used in the sequential controller.

throttle Not used in the sequential controller.

name Character string, name of the task. If NULL, then a random name is generated automatically. The name of the task must not conflict with the name of another task pushed to the controller. Any previous task with the same name must first be popped before a new task with that name can be pushed.

save_command Deprecated on 2025-01-22 (crew version 0.10.2.9004) and no longer used.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Invisibly returns a mirai-like list where the data element is the result of the task.

Method wait(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$wait(
  mode = "all",
  seconds_interval = NULL,
  seconds_timeout = Inf,
  scale = TRUE,
  throttle = TRUE,
  controllers = NULL
)
```

Arguments:

mode Not applicable to the sequential controller.

seconds_interval Not applicable to the sequential controller.

seconds_timeout Not applicable to the sequential controller.

scale Not applicable to the sequential controller.

throttle Not applicable to the sequential controller.

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Always returns TRUE (invisibly) for the sequential controller.

Method push_backlog(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$push_backlog(name, controller = NULL)
```

Arguments:

name Character of length 1 with the task name to push to the backlog.

controller Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

Method pop_backlog(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$pop_backlog(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: Always character(0L) for the sequential controller.

Method cancel(): Not applicable to the sequential controller.

Usage:

```
crew_class_controller_sequential$cancel(names = character(0L), all = FALSE)
```

Arguments:

names Not applicable to the sequential controller.

all Not applicable to the sequential controller.

Method terminate(): Terminate the controller.

Usage:

```
crew_class_controller_sequential$terminate(controllers = NULL)
```

Arguments:

controllers Not used. Included to ensure the signature is compatible with the analogous method of controller groups.

Returns: NULL (invisibly).

See Also

Other sequential controllers: [crew_controller_sequential\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  controller <- crew_controller_sequential()
  controller$push(name = "task", command = sqrt(4))
  controller$pop()
}
```

crew_class_launcher *Launcher abstract class*

Description

R6 abstract class to build other subclasses which launch and manage workers.

Active bindings

name See `crew_launcher()`.
 workers See `crew_launcher()`.
 seconds_interval See `crew_launcher()`.
 seconds_timeout See `crew_launcher()`.
 seconds_launch See `crew_launcher()`.
 seconds_idle See `crew_launcher()`.
 seconds_wall See `crew_launcher()`.
 tasks_max See `crew_launcher()`.
 tasks_timers See `crew_launcher()`.
 tls See `crew_launcher()`.
 r_arguments See `crew_launcher()`.
 options_metrics See `crew_launcher()`.
 url Websocket URL for worker connections.
 profile mirai compute profile of the launcher.
 launches Data frame tracking worker launches with one row per launch. Each launch may create more than one worker. Old superfluous rows are periodically discarded for efficiency.
 throttle A `crew_throttle()` object to throttle scaling.
 failed Number of failed worker launches (launches that exceed `seconds_launch` seconds to dial in).

Methods**Public methods:**

- `crew_class_launcher$new()`
- `crew_class_launcher$validate()`
- `crew_class_launcher$poll()`
- `crew_class_launcher$settings()`
- `crew_class_launcher$call()`
- `crew_class_launcher$start()`
- `crew_class_launcher$terminate()`
- `crew_class_launcher$launch()`
- `crew_class_launcher$launch_worker()`
- `crew_class_launcher$launch_workers()`
- `crew_class_launcher$scale()`
- `crew_class_launcher$terminate_workers()`
- `crew_class_launcher$crashes()`
- `crew_class_launcher$set_name()`
- `crew_class_launcher$clone()`

Method `new()`: Launcher constructor.

Usage:

```
crew_class_launcher$new(  
  name = NULL,  
  workers = NULL,  
  seconds_interval = NULL,  
  seconds_timeout = NULL,  
  seconds_launch = NULL,  
  seconds_idle = NULL,  
  seconds_wall = NULL,  
  seconds_exit = NULL,  
  tasks_max = NULL,  
  tasks_timers = NULL,  
  reset_globals = NULL,  
  reset_packages = NULL,  
  reset_options = NULL,  
  garbage_collection = NULL,  
  crashes_error = NULL,  
  launch_max = NULL,  
  tls = NULL,  
  processes = NULL,  
  r_arguments = NULL,  
  options_metrics = NULL  
)
```

Arguments:

name See [crew_launcher\(\)](#).
workers See [crew_launcher\(\)](#).
seconds_interval See [crew_launcher\(\)](#).
seconds_timeout See [crew_launcher\(\)](#).
seconds_launch See [crew_launcher\(\)](#).
seconds_idle See [crew_launcher\(\)](#).
seconds_wall See [crew_launcher\(\)](#).
seconds_exit See [crew_launcher\(\)](#).
tasks_max See [crew_launcher\(\)](#).
tasks_timers See [crew_launcher\(\)](#).
reset_globals Deprecated. See [crew_launcher\(\)](#).
reset_packages Deprecated. See [crew_launcher\(\)](#).
reset_options Deprecated. See [crew_launcher\(\)](#).
garbage_collection Deprecated. See [crew_launcher\(\)](#).
crashes_error See [crew_launcher\(\)](#).
launch_max Deprecated.
tls See [crew_launcher\(\)](#).
processes Deprecated on 2025-08-27 (crew version 1.2.1.9009).
r_arguments See [crew_launcher\(\)](#).
options_metrics See [crew_launcher\(\)](#).

Returns: An R6 object with the launcher.

Examples:

```

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local()
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}

```

Method `validate()`: Validate the launcher.

Usage:

```
crew_class_launcher$validate()
```

Returns: NULL (invisibly).

Method `poll()`: Poll the throttle.

Usage:

```
crew_class_launcher$poll()
```

Returns: TRUE to run whatever work comes next, FALSE to skip until the appropriate time.

Method `settings()`: List of arguments for `mirai::daemon()`.

Usage:

```
crew_class_launcher$settings()
```

Returns: List of arguments for `mirai::daemon()`.

Method `call()`: Create a call to `crew_worker()` to help create custom launchers.

Usage:

```
crew_class_launcher$call(worker = NULL)
```

Arguments:

`worker` Deprecated on 2025-08-28 (crew version 1.2.1.9009).

Returns: Character string with a call to `crew_worker()`.

Examples:

```

launcher <- crew_launcher_local()
launcher$start(url = "tcp://127.0.0.1:57000", profile = "profile")
launcher$call()
launcher$terminate()

```

Method `start()`: Start the launcher.

Usage:

```
crew_class_launcher$start(url = NULL, profile = NULL, sockets = NULL)
```

Arguments:

`url` Character string, websocket URL for worker connections.

`profile` Character string, mirai compute profile.

`sockets` Deprecated on 2025-01-28 (crew version 1.0.0).

Returns: NULL (invisibly).

Method `terminate()`: Terminate the whole launcher, including all workers.

Usage:

```
crew_class_launcher$terminate()
```

Returns: NULL (invisibly).

Method `launch()`: Launch a worker.

Usage:

```
crew_class_launcher$launch(n = 1L)
```

Arguments:

`n` Positive integer, number of workers to launch.

Returns: Handle of the launched worker.

Method `launch_worker()`: Abstract worker launch method.

Usage:

```
crew_class_launcher$launch_worker(call)
```

Arguments:

`call` Character of length 1 with a namespaced call to `crew_worker()` which will run in the worker and accept tasks.

Details: Launcher plugins will overwrite this method.

Returns: A handle to mock the worker launch.

Method `launch_workers()`: Launch multiple workers.

Usage:

```
crew_class_launcher$launch_workers(call, n)
```

Arguments:

`call` Character of length 1 with a namespaced call to `crew_worker()` which will run in each worker and accept tasks.

`n` Positive integer, number of workers to launch.

Details: Launcher plugins may overwrite this method to launch multiple workers from a single system call.

Returns: A handle to mock the worker launch.

Method `scale()`: Auto-scale workers out to meet the demand of tasks.

Usage:

```
crew_class_launcher$scale(status, throttle = NULL)
```

Arguments:

`status` A mirai status list with worker and task information.

`throttle` Deprecated, only used in the controller as of 2025-01-16 (crew version 0.10.2.9003).

Returns: Invisibly returns TRUE if there was any relevant auto-scaling activity (new worker launches or worker connection/disconnection events) (FALSE otherwise).

Method `terminate_workers()`: Deprecated on 2025-08-26 (crew version 1.2.1.9004).

Usage:

```
crew_class_launcher$terminate_workers()
```

Returns: NULL (invisibly).

Method `crashes()`: Deprecated on 2025-01-28 (crew version 1.0.0).

Usage:

```
crew_class_launcher$crashes(index = NULL)
```

Arguments:

`index` Unused argument.

Returns: The integer 1, for compatibility.

Method `set_name()`: Deprecated on 2025-01-28 (crew version 1.0.0).

Usage:

```
crew_class_launcher$set_name(name)
```

Arguments:

`name` Name to set for the launcher.

Returns: NULL (invisibly).

Method `clone()`: The objects of this class are cloneable with this method.

Usage:

```
crew_class_launcher$clone(deep = FALSE)
```

Arguments:

`deep` Whether to make a deep clone.

See Also

Other launcher: [crew_launcher\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local()
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}
```

```

}

## -----
## Method `crew_class_launcher$new`
## -----

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local()
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}

## -----
## Method `crew_class_launcher$call`
## -----

launcher <- crew_launcher_local()
launcher$start(url = "tcp://127.0.0.1:57000", profile = "profile")
launcher$call()
launcher$terminate()

```

```
crew_class_launcher_local
```

Local process launcher class

Description

R6 class to launch and manage local process workers.

Details

See [crew_launcher_local\(\)](#).

Super class

[crew::crew_class_launcher](#) -> crew_class_launcher_local

Active bindings

options_local See [crew_launcher_local\(\)](#).

Methods

Public methods:

- [crew_class_launcher_local\\$new\(\)](#)
- [crew_class_launcher_local\\$validate\(\)](#)
- [crew_class_launcher_local\\$launch_worker\(\)](#)
- [crew_class_launcher_local\\$clone\(\)](#)

Method `new()`: Local launcher constructor.

Usage:

```
crew_class_launcher_local$new(  
  name = NULL,  
  workers = NULL,  
  seconds_interval = NULL,  
  seconds_timeout = NULL,  
  seconds_launch = NULL,  
  seconds_idle = NULL,  
  seconds_wall = NULL,  
  seconds_exit = NULL,  
  tasks_max = NULL,  
  tasks_timers = NULL,  
  crashes_error = NULL,  
  tls = NULL,  
  processes = NULL,  
  r_arguments = NULL,  
  options_metrics = NULL,  
  options_local = NULL  
)
```

Arguments:

`name` See [crew_launcher\(\)](#).
`workers` See [crew_launcher\(\)](#).
`seconds_interval` See [crew_launcher\(\)](#).
`seconds_timeout` See [crew_launcher\(\)](#).
`seconds_launch` See [crew_launcher\(\)](#).
`seconds_idle` See [crew_launcher\(\)](#).
`seconds_wall` See [crew_launcher\(\)](#).
`seconds_exit` See [crew_launcher\(\)](#).
`tasks_max` See [crew_launcher\(\)](#).
`tasks_timers` See [crew_launcher\(\)](#).
`crashes_error` See [crew_launcher\(\)](#).
`tls` See [crew_launcher\(\)](#).
`processes` See [crew_launcher\(\)](#).
`r_arguments` See [crew_launcher\(\)](#).
`options_metrics` See [crew_launcher_local\(\)](#).
`options_local` See [crew_launcher_local\(\)](#).

[reset_globals](#) Deprecated. See [crew_launcher\(\)](#).
[reset_packages](#) Deprecated. See [crew_launcher\(\)](#).
[reset_options](#) Deprecated. See [crew_launcher\(\)](#).
[garbage_collection](#) Deprecated. See [crew_launcher\(\)](#).

Returns: An R6 object with the local launcher.

Examples:

```

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local(name = client$name)
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}
  
```

Method [validate\(\)](#): Validate the local launcher.

Usage:

```
crew_class_launcher_local$validate()
```

Returns: NULL (invisibly).

Method [launch_worker\(\)](#): Launch a local process worker which will dial into a socket.

Usage:

```
crew_class_launcher_local$launch_worker(call)
```

Arguments:

`call` Character of length 1 with a namespaced call to [crew_worker\(\)](#) which will run in the worker and accept tasks.

Details: The `call` argument is R code that will run to initiate the worker. Together, the launcher, worker, and instance arguments are useful for constructing informative job names.

Returns: A handle object to allow the termination of the worker later on.

Method [clone\(\)](#): The objects of this class are cloneable with this method.

Usage:

```
crew_class_launcher_local$clone(deep = FALSE)
```

Arguments:

`deep` Whether to make a deep clone.

See Also

Other plugin_local: [crew_controller_local\(\)](#), [crew_launcher_local\(\)](#)

Examples

```

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local(name = client$name)
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}

## -----
## Method `crew_class_launcher_local$new`
## -----

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local(name = client$name)
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}

```

```
crew_class_monitor_local
```

Local monitor class

Description

Local monitor R6 class

Details

See [crew_monitor_local\(\)](#).

Methods**Public methods:**

- [crew_class_monitor_local\\$dispatchers\(\)](#)
- [crew_class_monitor_local\\$daemons\(\)](#)
- [crew_class_monitor_local\\$workers\(\)](#)
- [crew_class_monitor_local\\$terminate\(\)](#)

Method `dispatchers()`: Deprecated: list the process IDs of the running mirai dispatcher processes. (No longer applicable.)

Usage:

```
crew_class_monitor_local$dispatchers(user = ps::ps_username())
```

Arguments:

`user` Character of length 1, user ID to filter on. NULL to list processes of all users (not recommended).

Details: The mirai dispatcher was an R process in mirai version $\leq 2.6.1$. In later versions, the dispatcher is a thread within the controller's own R process, and the `dispatchers()` method does not return any process IDs.

Returns: Integer vector of process IDs of the running mirai dispatcher processes.

Method `daemons()`: List the process IDs of the locally running mirai daemon processes which are not crew workers.

Usage:

```
crew_class_monitor_local$daemons(user = ps::ps_username())
```

Arguments:

`user` Character of length 1, user ID to filter on. NULL to list processes of all users (not recommended).

Returns: Integer vector of process IDs of the locally running mirai daemon processes which are not crew workers.

Method `workers()`: List the process IDs of locally running crew workers launched by the local controller ([crew_controller_local\(\)](#)).

Usage:

```
crew_class_monitor_local$workers(user = ps::ps_username())
```

Arguments:

`user` Character of length 1, user ID to filter on. NULL to list processes of all users (not recommended).

Details: Only the workers running on your local computer are listed. Workers that are not listed include jobs on job schedulers like SLURM or jobs on cloud services like AWS Batch. To monitor those worker processes, please consult the monitor objects in the relevant third-party launcher plugins such as `crew.cluster` and `crew.aws.batch`.

Returns: Integer vector of process IDs of locally running crew workers launched by the local controller ([crew_controller_local\(\)](#)).

Method `terminate()`: Terminate the given process IDs.

Usage:

```
crew_class_monitor_local$terminate(pids)
```

Arguments:

`pids` Integer vector of process IDs of local processes to terminate.

Details: Termination happens with the operating system signal given by [crew_terminate_signal\(\)](#).

Returns: NULL (invisibly).

See Also

Other monitor: [crew_monitor_local\(\)](#)

crew_class_relay R6 *relay class*.

Description

R6 class for relay configuration.

Details

See [crew_relay\(\)](#).

Active bindings

condition Main condition variable.
from Condition variable to relay from.
to Condition variable to relay to.
throttle A [crew_throttle\(\)](#) object for `wait()`.

Methods**Public methods:**

- [crew_class_relay\\$new\(\)](#)
- [crew_class_relay\\$validate\(\)](#)
- [crew_class_relay\\$start\(\)](#)
- [crew_class_relay\\$terminate\(\)](#)
- [crew_class_relay\\$set_from\(\)](#)
- [crew_class_relay\\$set_to\(\)](#)
- [crew_class_relay\\$wait\(\)](#)

Method `new()`: Relay constructor.

Usage:

```
crew_class_relay$new(throttle)
```

Arguments:

throttle A [crew_throttle\(\)](#) object.

Returns: A [crew_relay\(\)](#) object.

Method `validate()`: Validate the object.

Usage:

```
crew_class_relay$validate()
```

Returns: NULL (invisibly).

Method `start()`: Start the relay object.

Usage:

```
crew_class_relay$start()
```

Returns: NULL (invisibly).

Method `terminate()`: Terminate the relay object.

Usage:

```
crew_class_relay$terminate()
```

Returns: NULL (invisibly).

Method `set_from()`: Set the condition variable to relay from.

Usage:

```
crew_class_relay$set_from(from)
```

Arguments:

`from` Condition variable to relay from.

Returns: NULL (invisibly).

Method `set_to()`: Set the condition variable to relay to.

Usage:

```
crew_class_relay$set_to(to)
```

Arguments:

`to` Condition variable to relay to.

Returns: NULL (invisibly).

Method `wait()`: Wait until an unobserved task resolves or the timeout is reached. Use the throttle to determine the waiting time.

Usage:

```
crew_class_relay$wait()
```

Returns: NULL (invisibly).

See Also

Other relay: [crew_relay\(\)](#)

Examples

```
crew_relay()
```

crew_class_throttle R6 throttle class.

Description

R6 class for throttle configuration.

Details

See [crew_throttle\(\)](#).

Active bindings

seconds_max See [crew_throttle\(\)](#).

seconds_min See [crew_throttle\(\)](#).

seconds_start See [crew_throttle\(\)](#).

base See [crew_throttle\(\)](#).

seconds_interval Current wait time interval.

polled Positive numeric of length 1, millisecond timestamp of the last time `poll()` returned TRUE.
NULL if `poll()` was never called on the current object.

Methods

Public methods:

- [crew_class_throttle\\$new\(\)](#)
- [crew_class_throttle\\$validate\(\)](#)
- [crew_class_throttle\\$poll\(\)](#)
- [crew_class_throttle\\$accelerate\(\)](#)
- [crew_class_throttle\\$decelerate\(\)](#)
- [crew_class_throttle\\$reset\(\)](#)
- [crew_class_throttle\\$update\(\)](#)

Method `new()`: Throttle constructor.

Usage:

```
crew_class_throttle$new(  
  seconds_max = NULL,  
  seconds_min = NULL,  
  seconds_start = NULL,  
  base = NULL  
)
```

Arguments:

seconds_max See [crew_throttle\(\)](#).

seconds_min See [crew_throttle\(\)](#).

seconds_start See `crew_throttle()`.

base See `crew_throttle()`.

Returns: An R6 object with throttle configuration.

Examples:

```
throttle <- crew_throttle(seconds_max = 1)
throttle$poll()
throttle$poll()
```

Method `validate()`: Validate the object.

Usage:

```
crew_class_throttle$validate()
```

Returns: NULL (invisibly).

Method `poll()`: Poll the throttler.

Usage:

```
crew_class_throttle$poll()
```

Returns: TRUE if `poll()` did not return TRUE in the last max seconds, FALSE otherwise.

Method `accelerate()`: Divide `seconds_interval` by `base`.

Usage:

```
crew_class_throttle$accelerate()
```

Returns: NULL (invisibly). Called for its side effects.

Method `decelerate()`: Multiply `seconds_interval` by `base`.

Usage:

```
crew_class_throttle$decelerate()
```

Returns: NULL (invisibly). Called for its side effects.

Method `reset()`: Reset the throttle object so the next `poll()` returns TRUE, and reset the wait time interval to its initial value.

Usage:

```
crew_class_throttle$reset()
```

Returns: NULL (invisibly).

Method `update()`: Reset the throttle when there is activity and decelerate it gradually when there is no activity.

Usage:

```
crew_class_throttle$update(activity)
```

Arguments:

`activity` TRUE if there is activity, FALSE otherwise.

Returns: NULL (invisibly).

See Also

Other throttle: [crew_throttle\(\)](#)

Examples

```
throttle <- crew_throttle(seconds_max = 1)
throttle$poll()
throttle$poll()

## -----
## Method `crew_class_throttle$new`
## -----

throttle <- crew_throttle(seconds_max = 1)
throttle$poll()
throttle$poll()
```

crew_class_tls R6 TLS class.

Description

R6 class for TLS configuration.

Details

See [crew_tls\(\)](#).

Active bindings

mode See [crew_tls\(\)](#).

key See [crew_tls\(\)](#).

password See [crew_tls\(\)](#).

certificates See [crew_tls\(\)](#).

Methods**Public methods:**

- [crew_class_tls\\$new\(\)](#)
- [crew_class_tls\\$validate\(\)](#)
- [crew_class_tls\\$client\(\)](#)
- [crew_class_tls\\$worker\(\)](#)
- [crew_class_tls\\$url\(\)](#)

Method [new\(\)](#): TLS configuration constructor.

Usage:

```
crew_class_tls$new(  
  mode = NULL,  
  key = NULL,  
  password = NULL,  
  certificates = NULL  
)
```

Arguments:

mode Argument passed from `crew_tls()`.
key Argument passed from `crew_tls()`.
password Argument passed from `crew_tls()`.
certificates Argument passed from `crew_tls()`.

Returns: An R6 object with TLS configuration.

Examples:

```
crew_tls(mode = "automatic")
```

Method `validate()`: Validate the object.

Usage:

```
crew_class_tls$validate(test = TRUE)
```

Arguments:

test Logical of length 1, whether to test the TLS configuration with `nanonext::tls_config()`.

Returns: NULL (invisibly).

Method `client()`: TLS credentials for the crew client.

Usage:

```
crew_class_tls$client()
```

Returns: NULL or character vector, depending on the mode.

Method `worker()`: TLS credentials for crew workers.

Usage:

```
crew_class_tls$worker(profile)
```

Arguments:

profile Character of length 1 with the mirai compute profile.

Returns: NULL or character vector, depending on the mode.

Method `url()`: Form the URL for crew worker connections.

Usage:

```
crew_class_tls$url(host, port)
```

Arguments:

host Character string with the host name or IP address.

port Non-negative integer with the port number (0 to let NNG select a random ephemeral port).

Returns: Character string with the URL.

See Also

Other tls: [crew_tls\(\)](#)

Examples

```
crew_tls(mode = "automatic")

## -----
## Method `crew_class_tls$new`
## -----

crew_tls(mode = "automatic")
```

crew_clean

Deprecated: terminate dispatchers and/or workers

Description

Deprecated on 2025-08-26 in crew version 1.2.1.9006. Please use [crew_monitor_local\(\)](#) instead.

Usage

```
crew_clean(
  dispatchers = TRUE,
  workers = TRUE,
  user = ps::ps_username(),
  seconds_interval = 0.25,
  seconds_timeout = 60,
  verbose = TRUE
)
```

Arguments

dispatchers	Logical of length 1, whether to terminate dispatcher processes (in older versions of mirai: <= 2.6.1). In mirai > 2.6.1, the dispatcher is a thread within the controller's own R process and will not be terminated by this function.
workers	Logical of length 1, whether to terminate workers.
user	Character of length 1. Terminate processes associated with this user name.
seconds_interval	Seconds to wait between polling intervals waiting for a process to exit.
seconds_timeout	Seconds to wait for a process to exit.
verbose	Logical of length 1, whether to print an informative message every time a process is terminated.

Value

NULL (invisibly). If verbose is TRUE, it does print out a message for every terminated process.

See Also

Other utility: [crew_assert\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  crew_clean()
}
```

crew_client

Create a client object.

Description

Create an R6 wrapper object to manage the mirai client.

Usage

```
crew_client(
  name = NULL,
  workers = NULL,
  host = NULL,
  port = NULL,
  serialization = NULL,
  profile = crew::crew_random_name(),
  tls = crew::crew_tls(),
  tls_enable = NULL,
  tls_config = NULL,
  seconds_interval = 0.25,
  seconds_timeout = 60,
  retry_tasks = NULL
)
```

Arguments

name	Deprecated on 2025-01-14 (crew version 0.10.2.9002).
workers	Deprecated on 2025-01-13 (crew version 0.10.2.9002).
host	IP address of the mirai client to send and receive tasks. If NULL, the host defaults to <code>nanonext::ip_addr()[1]</code> .
port	TCP port to listen for the workers. If NULL, then an available ephemeral port is automatically chosen. Controllers running simultaneously on the same computer (as in a controller group) must not share the same TCP port.

serialization	Either NULL (default) or an object produced by <code>mirai::serial_config()</code> to control the serialization of data sent to workers. This can help with either more efficient data transfers or to preserve attributes of otherwise non-exportable objects (such as torch tensors or arrow tables). See <code>?mirai::serial_config</code> for details.
profile	Character string, compute profile for <code>mirai::daemons()</code> .
tls	A TLS configuration object from <code>crew_tls()</code> .
tls_enable	Deprecated on 2023-09-15 in version 0.4.1. Use argument <code>tls</code> instead.
tls_config	Deprecated on 2023-09-15 in version 0.4.1. Use argument <code>tls</code> instead.
seconds_interval	Number of seconds between polling intervals waiting for certain internal synchronous operations to complete, such as checking <code>mirai::info()</code>
seconds_timeout	Number of seconds until timing out while waiting for certain synchronous operations to complete, such as checking <code>mirai::info()</code> .
retry_tasks	Deprecated on 2025-01-13 (crew version 0.10.2.9002).

See Also

Other client: [crew_class_client](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  client$summary()
  client$terminate()
}
```

crew_controller

Create a controller object from a client and launcher.

Description

This function is for developers of crew launcher plugins. Users should use a specific controller helper such as [crew_controller_local\(\)](#).

Usage

```
crew_controller(
  client,
  launcher,
  reset_globals = TRUE,
  reset_packages = FALSE,
  reset_options = FALSE,
```

```

garbage_collection = FALSE,
crashes_max = 5L,
backup = NULL,
auto_scale = NULL
)

```

Arguments

client	An R6 client object created by <code>crew_client()</code> .
launcher	An R6 launcher object created by one of the <code>crew_launcher_*</code> () functions such as <code>crew_launcher_local()</code> .
reset_globals	TRUE to reset global environment variables between tasks, FALSE to leave them alone.
reset_packages	TRUE to detach any packages loaded during a task (runs between each task), FALSE to leave packages alone. In either case, the namespaces are not detached.
reset_options	TRUE to reset global options to their original state between each task, FALSE otherwise. It is recommended to only set <code>reset_options = TRUE</code> if <code>reset_packages</code> is also TRUE because packages sometimes rely on options they set at loading time. For this and other reasons, <code>reset_options</code> only resets options that were nonempty at the beginning of the task. If your task sets an entirely new option not already in <code>options()</code> , then <code>reset_options = TRUE</code> does not delete the option.
garbage_collection	TRUE to run garbage collection after each task, FALSE to skip.
crashes_max	In rare cases, a worker may exit unexpectedly before it completes its current task. If this happens, <code>pop()</code> returns a status of "crash" instead of "error" for the task. The controller does not automatically retry the task, but you can retry it manually by calling <code>push()</code> again and using the same task name as before. (However, targets pipelines running crew do automatically retry tasks whose workers crashed.) <code>crashes_max</code> is a non-negative integer, and it sets the maximum number of allowable consecutive crashes for a given task. If a task's worker crashes more than <code>crashes_max</code> times in a row, then <code>pop()</code> throws an error when it tries to return the results of the task.
backup	An optional crew controller object, or NULL to omit. If supplied, the backup controller runs any pushed tasks that have already reached <code>crashes_max</code> consecutive crashes. Using backup, you can create a chain of controllers with different levels of resources (such as worker memory and CPUs) so that a task that fails on one controller can retry using incrementally more powerful workers. All controllers in a backup chain should be part of the same controller group (see <code>crew_controller_group()</code>) so you can call the group-level <code>pop()</code> and <code>collect()</code> methods to make sure you get results regardless of which controller actually ended up running the task. Limitations of backup: * <code>crashes_max</code> needs to be positive in order for backup to be used. Otherwise, every task would always skip the current controller and go to backup. * backup cannot be a controller group. It must be an ordinary controller.

auto_scale Deprecated. Use the scale argument of push(), pop(), and wait() instead.

See Also

Other controller: [crew_class_controller](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  launcher <- crew_launcher_local()
  controller <- crew_controller(client = client, launcher = launcher)
  controller$start()
  controller$push(name = "task", command = sqrt(4))
  controller$wait()
  controller$pop()
  controller$terminate()
}
```

crew_controller_group *Create a controller group.*

Description

Create an R6 object to submit tasks and launch workers through multiple crew controllers.

Usage

```
crew_controller_group(..., seconds_interval = 0.25)
```

Arguments

... R6 controller objects or lists of R6 controller objects. Nested lists are allowed, but each element must be a control object or another list.

seconds_interval Number of seconds between polling intervals waiting for certain internal synchronous operations to complete, such as checking `mirai::info()`

See Also

Other controller_group: [crew_class_controller_group](#)

Examples

```

if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  persistent <- crew_controller_local(name = "persistent")
  transient <- crew_controller_local(
    name = "transient",
    tasks_max = 1L
  )
  group <- crew_controller_group(persistent, transient)
  group$start()
  group$push(name = "task", command = sqrt(4), controller = "transient")
  group$wait()
  group$pop()
  group$terminate()
}

```

crew_controller_local *Create a controller with a local process launcher.*

Description

Create an R6 object to submit tasks and launch workers on local processes.

Usage

```

crew_controller_local(
  name = NULL,
  workers = 1L,
  host = "127.0.0.1",
  port = NULL,
  tls = crew::crew_tls(),
  tls_enable = NULL,
  tls_config = NULL,
  serialization = NULL,
  profile = crew::crew_random_name(),
  seconds_interval = 0.25,
  seconds_timeout = 60,
  seconds_launch = 30,
  seconds_idle = 300,
  seconds_wall = Inf,
  seconds_exit = NULL,
  retry_tasks = NULL,
  tasks_max = Inf,
  tasks_timers = 0L,
  reset_globals = TRUE,
  reset_packages = FALSE,
  reset_options = FALSE,
  garbage_collection = FALSE,

```

```

    crashes_error = NULL,
    launch_max = NULL,
    r_arguments = c("--no-save", "--no-restore"),
    crashes_max = 5L,
    backup = NULL,
    options_metrics = crew::crew_options_metrics(),
    options_local = crew::crew_options_local(),
    local_log_directory = NULL,
    local_log_join = NULL
)

```

Arguments

name	Character string, name of the launcher. If the name is <code>NULL</code> , then a name is automatically generated when the launcher starts.
workers	Maximum number of workers to run concurrently when auto-scaling, excluding task retries and manual calls to <code>launch()</code> . Special workers allocated for task retries do not count towards this limit, so the number of workers running at a given time may exceed this maximum. A smaller number of workers may run if the number of executing tasks is smaller than the supplied value of the <code>workers</code> argument.
host	IP address of the <code>mirai</code> client to send and receive tasks. If <code>NULL</code> , the host defaults to <code>nanonext::ip_addr()[1]</code> .
port	TCP port to listen for the workers. If <code>NULL</code> , then an available ephemeral port is automatically chosen. Controllers running simultaneously on the same computer (as in a controller group) must not share the same TCP port.
tls	A TLS configuration object from <code>crew_tls()</code> .
tls_enable	Deprecated on 2023-09-15 in version 0.4.1. Use argument <code>tls</code> instead.
tls_config	Deprecated on 2023-09-15 in version 0.4.1. Use argument <code>tls</code> instead.
serialization	Either <code>NULL</code> (default) or an object produced by <code>mirai::serial_config()</code> to control the serialization of data sent to workers. This can help with either more efficient data transfers or to preserve attributes of otherwise non-exportable objects (such as <code>torch</code> tensors or <code>arrow</code> tables). See <code>?mirai::serial_config</code> for details.
profile	Character string, compute profile for <code>mirai::daemons()</code> .
seconds_interval	Number of seconds between polling intervals waiting for certain internal synchronous operations to complete. In certain cases, exponential backoff is used with this argument passed to <code>seconds_max</code> in a <code>crew_throttle()</code> object.
seconds_timeout	Number of seconds until timing out while waiting for certain synchronous operations to complete, such as checking <code>mirai::info()</code> .
seconds_launch	Seconds of startup time to allow. A worker is unconditionally assumed to be alive from the moment of its launch until <code>seconds_launch</code> seconds later. After <code>seconds_launch</code> seconds, the worker is only considered alive if it is actively connected to its assign websocket.

seconds_idle	Maximum number of seconds that a worker can idle since the completion of the last task. If exceeded, the worker exits. But the timer does not launch until <code>tasks_timers</code> tasks have completed. See the <code>idleTime</code> argument of <code>mirai::daemon()</code> . crew does not excel with perfectly transient workers because it does not micro-manage the assignment of tasks to workers, so please allow enough idle time for a new worker to be delegated a new task.
seconds_wall	Soft wall time in seconds. The timer does not launch until <code>tasks_timers</code> tasks have completed. See the <code>wallTime</code> argument of <code>mirai::daemon()</code> .
seconds_exit	Deprecated on 2023-09-21 in version 0.5.0.9002. No longer necessary.
retry_tasks	Deprecated on 2025-01-13 (crew version 0.10.2.9002).
tasks_max	Maximum number of tasks that a worker will do before exiting. Also determines how often the controller auto-scales. See the Auto-scaling section for details.
tasks_timers	Number of tasks to do before activating the timers for <code>seconds_idle</code> and <code>seconds_wall</code> . See the <code>timerStart</code> argument of <code>mirai::daemon()</code> .
reset_globals	TRUE to reset global environment variables between tasks, FALSE to leave them alone.
reset_packages	TRUE to detach any packages loaded during a task (runs between each task), FALSE to leave packages alone. In either case, the namespaces are not detached.
reset_options	TRUE to reset global options to their original state between each task, FALSE otherwise. It is recommended to only set <code>reset_options = TRUE</code> if <code>reset_packages</code> is also TRUE because packages sometimes rely on options they set at loading time. for this and other reasons, <code>reset_options</code> only resets options that were nonempty at the beginning of the task. If your task sets an entirely new option not already in <code>options()</code> , then <code>reset_options = TRUE</code> does not delete the option.
garbage_collection	TRUE to run garbage collection after each task task, FALSE to skip.
crashes_error	Deprecated on 2025-01-13 (crew version 0.10.2.9002).
launch_max	Deprecated on 2024-11-04 (crew version 0.10.2.9002).
r_arguments	Optional character vector of command line arguments to pass to <code>Rscript</code> (non-Windows) or <code>Rscript.exe</code> (Windows) when starting a worker. Example: <code>r_arguments = c("--vanilla", "--max-connections=32")</code> .
crashes_max	In rare cases, a worker may exit unexpectedly before it completes its current task. If this happens, <code>pop()</code> returns a status of "crash" instead of "error" for the task. The controller does not automatically retry the task, but you can retry it manually by calling <code>push()</code> again and using the same task name as before. (However, targets pipelines running crew do automatically retry tasks whose workers crashed.) <code>crashes_max</code> is a non-negative integer, and it sets the maximum number of allowable consecutive crashes for a given task. If a task's worker crashes more than <code>crashes_max</code> times in a row, then <code>pop()</code> throws an error when it tries to return the results of the task.
backup	An optional crew controller object, or NULL to omit. If supplied, the backup controller runs any pushed tasks that have already reached <code>crashes_max</code> consecutive crashes. Using <code>backup</code> , you can create a chain of controllers with different levels of resources (such as worker memory and CPUs) so that a task that

fails on one controller can retry using incrementally more powerful workers. All controllers in a backup chain should be part of the same controller group (see `crew_controller_group()`) so you can call the group-level `pop()` and `collect()` methods to make sure you get results regardless of which controller actually ended up running the task.

Limitations of backup: * `crashes_max` needs to be positive in order for backup to be used. Otherwise, every task would always skip the current controller and go to backup. * backup cannot be a controller group. It must be an ordinary controller.

options_metrics

Either NULL to opt out of resource metric logging for workers, or an object from `crew_options_metrics()` to enable and configure resource metric logging for workers. For resource logging to run, the `autometric` R package version 0.1.0 or higher must be installed.

`options_local` An object generated by `crew_options_local()` with options specific to the local controller.

local_log_directory

Deprecated on 2024-10-08. Use `options_local` instead.

`local_log_join` Deprecated on 2024-10-08. Use `options_local` instead.

See Also

Other plugin_local: `crew_class_launcher_local`, `crew_launcher_local()`

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  controller <- crew_controller_local()
  controller$start()
  controller$push(name = "task", command = sqrt(4))
  controller$wait()
  controller$pop()
  controller$terminate()
}
```

crew_controller_sequential

Create a sequential controller.

Description

The sequential controller runs tasks on the same R process where the controller object exists. Tasks run sequentially rather than in parallel.

Usage

```
crew_controller_sequential(
  reset_globals = TRUE,
  reset_packages = FALSE,
  reset_options = FALSE,
  garbage_collection = FALSE
)
```

Arguments

`reset_globals` TRUE to reset global environment variables between tasks, FALSE to leave them alone.

`reset_packages` TRUE to detach any packages loaded during a task (runs between each task), FALSE to leave packages alone. In either case, the namespaces are not detached.

`reset_options` TRUE to reset global options to their original state between each task, FALSE otherwise. It is recommended to only set `reset_options = TRUE` if `reset_packages` is also TRUE because packages sometimes rely on options they set at loading time. For this and other reasons, `reset_options` only resets options that were nonempty at the beginning of the task. If your task sets an entirely new option not already in `options()`, then `reset_options = TRUE` does not delete the option.

`garbage_collection` TRUE to run garbage collection after each task task, FALSE to skip.

See Also

Other sequential controllers: [crew_class_controller_sequential](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  controller <- crew_controller_sequential()
  controller$push(name = "task", command = sqrt(4))
  controller$pop()
}
```

crew_deprecate

Deprecate a crew feature.

Description

Show an informative warning when a crew feature is deprecated.

Usage

```
crew_deprecate(  
  name,  
  date,  
  version,  
  alternative,  
  condition = "warning",  
  value = "x",  
  skip_cran = FALSE,  
  frequency = "always"  
)
```

Arguments

name	Name of the feature (function or argument) to deprecate.
date	Date of deprecation.
version	Package version when deprecation was instated.
alternative	Message about an alternative.
condition	Either "warning" or "message" to indicate the type of condition thrown on deprecation.
value	Value of the object. Deprecation is skipped if value is NULL.
skip_cran	Logical of length 1, whether to skip the deprecation warning or message on CRAN.
frequency	Character of length 1, passed to the .frequency argument of rlang::warn().

Value

NULL (invisibly). Throws a warning if a feature is deprecated.

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
suppressWarnings(  
  crew_deprecate(  
    name = "auto_scale",  
    date = "2023-05-18",  
    version = "0.2.0",  
    alternative = "use the scale argument of push(), pop(), and wait()."  
  )  
)
```

crew_eval

Evaluate an R command and return results as a monad.

Description

Not a user-side function. Do not call directly.

Usage

```
crew_eval(
  command,
  name,
  data = list(),
  globals = list(),
  seed = NULL,
  algorithm = NULL,
  packages = character(),
  library = NULL,
  reset_globals = TRUE,
  reset_packages = FALSE,
  reset_options = FALSE,
  garbage_collection = FALSE
)
```

Arguments

command	Language object with R code to run.
name	Character of length 1, name of the task.
data	Named list of local data objects in the evaluation environment.
globals	Named list of objects to temporarily assign to the global environment for the task.
seed	Integer of length 1 with the pseudo-random number generator seed to set for the evaluation of the task. Passed to the seed argument of <code>set.seed()</code> if not NULL. If <code>algorithm</code> and <code>seed</code> are both NULL, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by <code>mirai::nextstream()</code> . See <code>vignette("parallel", package = "parallel")</code> for details.
algorithm	Integer of length 1 with the pseudo-random number generator algorithm to set for the evaluation of the task. Passed to the kind argument of <code>RNGkind()</code> if not NULL. If <code>algorithm</code> and <code>seed</code> are both NULL, then the random number generator defaults to the recommended widely spaced worker-specific L'Ecuyer streams as supported by <code>mirai::nextstream()</code> . See <code>vignette("parallel", package = "parallel")</code> for details.
packages	Character vector of packages to load for the task.
library	Library path to load the packages. See the <code>lib.loc</code> argument of <code>require()</code> .

- `reset_globals` TRUE to reset global environment variables between tasks, FALSE to leave them alone.
- `reset_packages` TRUE to detach any packages loaded during a task (runs between each task), FALSE to leave packages alone. In either case, the namespaces are not detached.
- `reset_options` TRUE to reset global options to their original state between each task, FALSE otherwise. It is recommended to only set `reset_options = TRUE` if `reset_packages` is also TRUE because packages sometimes rely on options they set at loading time. For this and other reasons, `reset_options` only resets options that were nonempty at the beginning of the task. If your task sets an entirely new option not already in `options()`, then `reset_options = TRUE` does not delete the option.
- `garbage_collection`
TRUE to run garbage collection after each task task, FALSE to skip.

Details

The `crew_eval()` function evaluates an R expression in an encapsulated environment and returns a monad with the results, including warnings and error messages if applicable. The random number generator seed, globals, and global options are restored to their original values on exit.

Value

A monad object with results and metadata.

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
crew_eval(quote(1 + 1), name = "task_name")
```

crew_launcher

Create an abstract launcher.

Description

This function is useful for inheriting argument documentation in functions that create custom third-party launchers. See `@inheritParams crew::crew_launcher` in the source code file of [crew_launcher_local\(\)](#).

Usage

```

crew_launcher(
  name = NULL,
  workers = 1L,
  seconds_interval = 0.25,
  seconds_timeout = 60,
  seconds_launch = 30,
  seconds_idle = 300,
  seconds_wall = Inf,
  seconds_exit = NULL,
  tasks_max = Inf,
  tasks_timers = 0L,
  reset_globals = NULL,
  reset_packages = NULL,
  reset_options = NULL,
  garbage_collection = NULL,
  crashes_error = NULL,
  launch_max = NULL,
  tls = crew::crew_tls(),
  processes = NULL,
  r_arguments = c("--no-save", "--no-restore"),
  options_metrics = crew::crew_options_metrics()
)

```

Arguments

name	Character string, name of the launcher. If the name is NULL, then a name is automatically generated when the launcher starts.
workers	Maximum number of workers to run concurrently when auto-scaling, excluding task retries and manual calls to <code>launch()</code> . Special workers allocated for task retries do not count towards this limit, so the number of workers running at a given time may exceed this maximum. A smaller number of workers may run if the number of executing tasks is smaller than the supplied value of the workers argument.
seconds_interval	Number of seconds between polling intervals waiting for certain internal synchronous operations to complete. In certain cases, exponential backoff is used with this argument passed to <code>seconds_max</code> in a <code>crew_throttle()</code> object.
seconds_timeout	Number of seconds until timing out while waiting for certain synchronous operations to complete, such as checking <code>mirai::info()</code> .
seconds_launch	Seconds of startup time to allow. A worker is unconditionally assumed to be alive from the moment of its launch until <code>seconds_launch</code> seconds later. After <code>seconds_launch</code> seconds, the worker is only considered alive if it is actively connected to its assign websocket.
seconds_idle	Maximum number of seconds that a worker can idle since the completion of the last task. If exceeded, the worker exits. But the timer does not launch until

	tasks_timers tasks have completed. See the <code>idletime</code> argument of <code>mirai::daemon()</code> . crew does not excel with perfectly transient workers because it does not micro-manage the assignment of tasks to workers, so please allow enough idle time for a new worker to be delegated a new task.
<code>seconds_wall</code>	Soft wall time in seconds. The timer does not launch until <code>tasks_timers</code> tasks have completed. See the <code>walltime</code> argument of <code>mirai::daemon()</code> .
<code>seconds_exit</code>	Deprecated on 2023-09-21 in version 0.5.0.9002. No longer necessary.
<code>tasks_max</code>	Maximum number of tasks that a worker will do before exiting. Also determines how often the controller auto-scales. See the Auto-scaling section for details.
<code>tasks_timers</code>	Number of tasks to do before activating the timers for <code>seconds_idle</code> and <code>seconds_wall</code> . See the <code>timerstart</code> argument of <code>mirai::daemon()</code> .
<code>reset_globals</code>	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_globals</code> option of <code>crew_controller()</code> instead.
<code>reset_packages</code>	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_packages</code> option of <code>crew_controller()</code> instead.
<code>reset_options</code>	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_options</code> option of <code>crew_controller()</code> instead.
<code>garbage_collection</code>	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>garbage_collection</code> option of <code>crew_controller()</code> instead.
<code>crashes_error</code>	Deprecated on 2025-01-13 (crew version 0.10.2.9002).
<code>launch_max</code>	Deprecated on 2024-11-04 (crew version 0.10.2.9002).
<code>tls</code>	A TLS configuration object from <code>crew_tls()</code> .
<code>processes</code>	Deprecated on 2025-08-27 (crew version 1.2.1.9009).
<code>r_arguments</code>	Optional character vector of command line arguments to pass to <code>Rscript</code> (non-Windows) or <code>Rscript.exe</code> (Windows) when starting a worker. Example: <code>r_arguments = c("--vanilla", "--max-connections=32")</code> .
<code>options_metrics</code>	Either <code>NULL</code> to opt out of resource metric logging for workers, or an object from <code>crew_options_metrics()</code> to enable and configure resource metric logging for workers. For resource logging to run, the <code>autometric</code> R package version 0.1.0 or higher must be installed.

Auto-scaling

crew launchers implement auto-scaling in the `scale()` method. When the task load increases, the number of workers increases in response to demand. When the task load decreases, the workers start to exit. This behavior happens dynamically over the course of a workflow, and it can be tuned with arguments `seconds_interval`, `seconds_wall`, and `tasks_max`.

`tasks_max` is special: it determines not only the number of tasks a worker runs before exiting, it also determines how often auto-scaling runs. If `tasks_max` is finite, then crew uses an aggressive deterministic exponential backoff algorithm to determine how frequently to auto-scale (see `crew_throttle()`). But if `tasks_max` is `Inf`, then crew only scales at equally-spaced time intervals of `seconds_interval` to allow enough pending tasks to accumulate for job arrays. This last part is important because auto-scaling too frequently could lead to hundreds of separate job arrays with only job per array (as opposed to the desired outcome of 1 or 2 arrays with many jobs each).

See Also

Other launcher: [crew_class_launcher](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local()
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}
```

crew_launcher_local *Create a launcher with local process workers.*

Description

Create an R6 object to launch and maintain local process workers.

Usage

```
crew_launcher_local(
  name = NULL,
  workers = 1L,
  seconds_interval = 0.25,
  seconds_timeout = 60,
  seconds_launch = 30,
  seconds_idle = Inf,
  seconds_wall = Inf,
  seconds_exit = NULL,
  tasks_max = Inf,
  tasks_timers = 0L,
  reset_globals = NULL,
  reset_packages = NULL,
  reset_options = NULL,
  garbage_collection = NULL,
  crashes_error = NULL,
  launch_max = NULL,
  tls = crew::crew_tls(),
  r_arguments = c("--no-save", "--no-restore"),
  options_metrics = crew::crew_options_metrics(),
  options_local = crew::crew_options_local(),
  local_log_directory = NULL,
```

```

    local_log_join = NULL
)

```

Arguments

name	Character string, name of the launcher. If the name is NULL, then a name is automatically generated when the launcher starts.
workers	Maximum number of workers to run concurrently when auto-scaling, excluding task retries and manual calls to <code>launch()</code> . Special workers allocated for task retries do not count towards this limit, so the number of workers running at a given time may exceed this maximum. A smaller number of workers may run if the number of executing tasks is smaller than the supplied value of the workers argument.
seconds_interval	Number of seconds between polling intervals waiting for certain internal synchronous operations to complete. In certain cases, exponential backoff is used with this argument passed to <code>seconds_max</code> in a <code>crew_throttle()</code> object.
seconds_timeout	Number of seconds until timing out while waiting for certain synchronous operations to complete, such as checking <code>mirai::info()</code> .
seconds_launch	Seconds of startup time to allow. A worker is unconditionally assumed to be alive from the moment of its launch until <code>seconds_launch</code> seconds later. After <code>seconds_launch</code> seconds, the worker is only considered alive if it is actively connected to its assign websocket.
seconds_idle	Maximum number of seconds that a worker can idle since the completion of the last task. If exceeded, the worker exits. But the timer does not launch until <code>tasks_timers</code> tasks have completed. See the <code>idletime</code> argument of <code>mirai::daemon()</code> . <code>crew</code> does not excel with perfectly transient workers because it does not micro-manage the assignment of tasks to workers, so please allow enough idle time for a new worker to be delegated a new task.
seconds_wall	Soft wall time in seconds. The timer does not launch until <code>tasks_timers</code> tasks have completed. See the <code>walltime</code> argument of <code>mirai::daemon()</code> .
seconds_exit	Deprecated on 2023-09-21 in version 0.5.0.9002. No longer necessary.
tasks_max	Maximum number of tasks that a worker will do before exiting. Also determines how often the controller auto-scales. See the Auto-scaling section for details.
tasks_timers	Number of tasks to do before activating the timers for <code>seconds_idle</code> and <code>seconds_wall</code> . See the <code>timerstart</code> argument of <code>mirai::daemon()</code> .
reset_globals	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_globals</code> option of <code>crew_controller()</code> instead.
reset_packages	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_packages</code> option of <code>crew_controller()</code> instead.
reset_options	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>reset_options</code> option of <code>crew_controller()</code> instead.
garbage_collection	Deprecated on 2025-05-30 (crew version 1.1.2.9004). Please use the <code>garbage_collection</code> option of <code>crew_controller()</code> instead.

crashes_error	Deprecated on 2025-01-13 (crew version 0.10.2.9002).
launch_max	Deprecated on 2024-11-04 (crew version 0.10.2.9002).
tls	A TLS configuration object from crew_tls() .
r_arguments	Optional character vector of command line arguments to pass to Rscript (non-Windows) or Rscript.exe (Windows) when starting a worker. Example: <code>r_arguments = c("--vanilla", "--max-connections=32")</code> .
options_metrics	Either NULL to opt out of resource metric logging for workers, or an object from crew_options_metrics() to enable and configure resource metric logging for workers. For resource logging to run, the autometric R package version 0.1.0 or higher must be installed.
options_local	An object generated by crew_options_local() with options specific to the local controller.
local_log_directory	Deprecated on 2024-10-08. Use <code>options_local</code> instead.
local_log_join	Deprecated on 2024-10-08. Use <code>options_local</code> instead.

See Also

Other plugin_local: [crew_class_launcher_local](#), [crew_controller_local\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {
  client <- crew_client()
  client$start()
  launcher <- crew_launcher_local(name = client$name)
  launcher$start(url = client$url, profile = client$profile)
  launcher$launch()
  task <- mirai::mirai("result", .compute = client$profile)
  mirai::call_mirai(task)
  task$data
  client$terminate()
}
```

crew_monitor_local *Create a local monitor object.*

Description

Create an R6 object to monitor local processes created by crew and mirai.

Usage

```
crew_monitor_local()
```

See Also

Other monitor: [crew_class_monitor_local](#)

crew_options_local *Local crew launcher options.*

Description

Options for the local crew launcher.

Usage

```
crew_options_local(log_directory = NULL, log_join = TRUE)
```

Arguments

`log_directory` Either NULL or a character of length 1 with the file path to a directory to write worker-specific log files with standard output and standard error messages. Each log file represents a single *instance* of a running worker, so there will be more log files if a given worker starts and terminates a lot. Set to NULL to suppress log files (default).

`log_join` Logical of length 1. If TRUE, crew will write standard output and standard error to the same log file for each worker instance. If FALSE, then they these two streams will go to different log files with informative suffixes.

Value

A classed list of options for the local launcher.

See Also

Other options: [crew_options_metrics\(\)](#)

Examples

```
crew_options_local()
```

crew_options_metrics *Options for logging resource usage metrics.*

Description

[crew_options_metrics\(\)](#) configures the crew to record resource usage metrics (such as CPU and memory usage) for each running worker. To be activate resource usage logging, the `autometric` R package version 0.1.0 or higher must be installed.

Logging happens in the background (through a detached POSIX) so as not to disrupt the R session. On Unix-like systems, [crew_options_metrics\(\)](#) can specify `/dev/stdout` or `/dev/stderr` as the log files, which will redirect output to existing logs you are already using. [autometric::log_read\(\)](#) and [autometric::log_plot\(\)](#) can read and visualize resource usage data from multiple log files, even if those files are mixed with other messages.

Usage

```
crew_options_metrics(path = NULL, seconds_interval = 5)
```

Arguments

path Where to write resource metric log entries for workers. `path = NULL` disables logging. `path` equal to `"/dev/stdout"` (or `"/dev/stderr"`) sends log messages to the standard output (or standard error) streams, which is recommended on Unix-like systems because then output will go to the existing log files already configured for the controller, e.g. through `crew_options_local()` in the case of `crew_controller_local()`. If `path` is not `NULL`, `"/dev/stdout"`, or `"/dev/stderr"`, it should be a directory path, in which case each worker instance will write to a new file in that directory.

After running enough tasks in crew, you can call `autometric::log_read(path)` to read all the data from all the log files in the files or directories at `path`, even if the logs files are mixed with other kinds of messages. Pass that data into `autometric::log_plot()` to visualize it.

seconds_interval Positive number, seconds between resource metric log entries written to `path`.

Value

A classed list of options for logging resource usage metrics.

See Also

Other options: `crew_options_local()`

Examples

```
crew_options_metrics()
```

crew_random_name	<i>Random name</i>
------------------	--------------------

Description

Generate a random string that can be used as a name for a worker or task.

Usage

```
crew_random_name(n = 8L)
```

Arguments

n Number of bytes of information in the random string hashed to generate the name. Larger `n` is more likely to generate unique names, but it may be slower to compute.

Details

The randomness is not reproducible and cannot be set with e.g. `set.seed()` in R.

Value

A random character string.

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
crew_random_name()
```

crew_relay	<i>Create a crew relay object.</i>
------------	------------------------------------

Description

Create an R6 crew relay object.

Usage

```
crew_relay(throttle = crew_throttle())
```

Arguments

`throttle` A [crew_throttle\(\)](#) object.

Details

A crew relay object keeps the signaling relationships among condition variables.

Value

An R6 crew relay object.

See Also

Other relay: [crew_class_relay](#)

Examples

```
crew_relay()
```

crew_retry

Retry code.

Description

Repeatedly retry a function while it keeps returning FALSE and exit the loop when it returns TRUE

Usage

```
crew_retry(
  fun,
  args = list(),
  seconds_interval = 0.25,
  seconds_timeout = 60,
  max_tries = Inf,
  error = TRUE,
  message = character(0),
  envir = parent.frame(),
  assertions = TRUE
)
```

Arguments

fun	Function that returns FALSE to keep waiting or TRUE to stop waiting.
args	A named list of arguments to fun.
seconds_interval	Nonnegative numeric of length 1, number of seconds to wait between calls to fun.
seconds_timeout	Nonnegative numeric of length 1, number of seconds to loop before timing out.
max_tries	Maximum number of calls to fun to try before giving up.
error	Whether to throw an error on a timeout or max tries.
message	Character of length 1, optional error message if the wait times out.
envir	Environment to evaluate fun.
assertions	TRUE to run assertions to check if arguments are valid, FALSE otherwise. TRUE is recommended for users.

Value

NULL (invisibly).

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_terminate_process\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
crew_retry(fun = function() TRUE)
```

crew_terminate_process

Manually terminate a local process.

Description

Manually terminate a local process.

Usage

```
crew_terminate_process(pid)
```

Arguments

pid Integer of length 1, process ID to terminate.

Value

NULL (invisibly).

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_signal\(\)](#), [crew_worker\(\)](#)

Examples

```
if (identical(Sys.getenv("CREW_EXAMPLES"), "true")) {  
  process <- processx::process$new("sleep", "60")  
  process$is_alive()  
  crew_terminate_process(pid = process$get_pid())  
  process$is_alive()  
}
```

crew_terminate_signal *Get the termination signal.*

Description

Get a supported operating system signal for terminating a local process.

Usage

```
crew_terminate_signal()
```

Value

An integer of length 1: `tools::SIGTERM` if your platform supports `SIGTERM`. If not, then `crew_terminate_signal()` checks `SIGQUIT`, then `SIGINT`, then `SIGKILL`, and then returns the first signal it finds that your operating system can use.

See Also

Other utility: [crew_assert\(\)](#), [crew_clean\(\)](#), [crew_deprecate\(\)](#), [crew_eval\(\)](#), [crew_random_name\(\)](#), [crew_retry\(\)](#), [crew_terminate_process\(\)](#), [crew_worker\(\)](#)

Examples

```
crew_terminate_signal()
```

crew_throttle *Create a stateful throttling object.*

Description

Create an R6 object for throttling.

Usage

```
crew_throttle(  
  seconds_max = 1,  
  seconds_min = 1e-06,  
  seconds_start = seconds_min,  
  base = 2  
)
```

Arguments

seconds_max	Positive numeric scalar, maximum throttling interval
seconds_min	Positive numeric scalar, minimum throttling interval.
seconds_start	Positive numeric scalar, the initial wait time interval in seconds. The default is min because there is almost always auto-scaling to be done when the controller is created. <code>reset()</code> always sets the current wait interval back to <code>seconds_start</code> .
base	Numeric scalar greater than 1, base of the exponential backoff algorithm. <code>increment()</code> multiplies the waiting interval by base and <code>decrement()</code> divides the waiting interval by base. The default base is 2, which specifies a binary exponential backoff algorithm.

Details

Throttling is a technique that limits how often a function is called in a given period of time. `crew_throttle()` objects support the `throttle` argument of controller methods, which ensures auto-scaling does not induce superfluous overhead. The throttle uses deterministic exponential backoff algorithm (https://en.wikipedia.org/wiki/Exponential_backoff) which increases wait times when there is nothing to do and decreases wait times when there is something to do. The controller decreases or increases the wait time with methods `accelerate()` and `decelerate()` in the throttle object, respectively, by dividing or multiplying by base (but keeping the wait time between `seconds_min` and `seconds_max`). In practice, crew calls `reset()` instead of `update()` in order to respond quicker to surges of activity (see the `update()` method).

Value

An R6 object with throttle configuration settings and methods.

See Also

Other throttle: `crew_class_throttle`

Examples

```
throttle <- crew_throttle(seconds_max = 1)
throttle$poll()
throttle$poll()
```

crew_tls

Configure TLS.

Description

Create an R6 object with transport layer security (TLS) configuration for crew.

Usage

```
crew_tls(
  mode = "none",
  key = NULL,
  password = NULL,
  certificates = NULL,
  validate = TRUE
)
```

Arguments

mode	Character of length 1. Must be one of the following: <ul style="list-style-type: none"> • "none": disable TLS configuration. • "automatic": let mirai create a one-time key pair with a self-signed certificate. • "custom": manually supply a private key pair, an optional password for the private key, a certificate, an optional revocation list.
key	If mode is "none" or "automatic", then key is NULL. If mode is "custom", then key is a character of length 1 with the file path to the private key file.
password	If mode is "none" or "automatic", then password is NULL. If mode is "custom" and the private key is not encrypted, then password is still NULL. If mode is "custom" and the private key is encrypted, then password is a character of length 1 the the password of the private key. In this case, DO NOT SAVE THE PASSWORD IN YOUR R CODE FILES. See the keyring R package for solutions.
certificates	If mode is "none" or "automatic", then certificates is NULL. If mode is "custom", then certificates is a character vector of file paths to certificate files (signed public keys). If the certificate is self-signed or if it is directly signed by a certificate authority (CA), then only the certificate of the CA is needed. But if you have a whole certificate chain which begins at your own certificate and ends with the CA, then you can supply the whole certificate chain as a character vector of file paths, beginning at your own certificate and ending with the certificate of the CA.
validate	Logical of length 1, whether to validate the configuration object on creation. If FALSE, then validate() can be called later on.

Details

`crew_tls()` objects are input to the `tls` argument of `crew_client()`, `crew_controller_local()`, etc. See <https://wlandau.github.io/crew/articles/risks.html> for details.

Value

An R6 object with TLS configuration settings and methods.

See Also

Other `tls`: [crew_class_tls](#)

Examples

```
crew_tls(mode = "automatic")
```

crew_worker

Crew worker.

Description

Launches a crew worker which runs a mirai daemon. Not a user-side function. Users should not call `crew_worker()` directly. See launcher plugins like `crew_launcher_local()` for examples.

Usage

```
crew_worker(  
  settings,  
  controller,  
  options_metrics = crew::crew_options_metrics()  
)
```

Arguments

settings	Named list of arguments to <code>mirai::daemon()</code> .
controller	Character string, name of the controller.
options_metrics	Either NULL to opt out of resource metric logging for workers, or an object from <code>crew_options_metrics()</code> to enable and configure resource metric logging for workers. For resource logging to run, the <code>autometric</code> R package version 0.1.0 or higher must be installed.

Value

NULL (invisibly)

See Also

Other utility: `crew_assert()`, `crew_clean()`, `crew_deprecate()`, `crew_eval()`, `crew_random_name()`, `crew_retry()`, `crew_terminate_process()`, `crew_terminate_signal()`

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