Distributed Systems

Time

Overview

- Time service
  - requirements and problems
  - sources of time
- Clock synchronisation algorithms
  - clock skew & drift
  - Cristian algorithm
  - Berkeley algorithm
  - Network Time Protocol
- Logical clocks
  - Lamport's timestamps

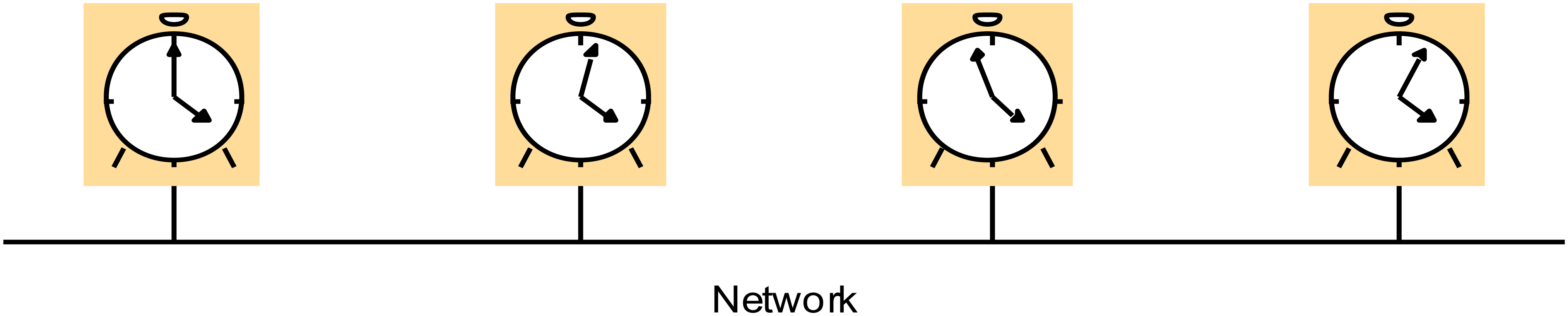
Time service

- Why needed?
  - to measure delays between distributed components
  - to synchronise streams, e.g. sound and video
  - to establish event ordering
    - causal ordering (did A happen before B?)
    - concurrent/overlapping execution (no causal relationship)
  - for accurate timestamps to identify/authenticate
    - business transactions
    - serializability in distributed databases
    - security protocols

Clocks

- Internal hardware clock
  - built-in electronic device
  - counts oscillations occurring in a quartz crystal at a definite frequency
  - store the result in a counter register
  - interrupt generated at regular intervals
  - interrupt handler reads the counter register, scales it to convert to time units (seconds, nanoseconds) and updates software clock

Clock skew and drift



- Clock skew
  - difference between the readings of two clocks
- Clock drift
  - difference in reading between a clock and a nominal perfect reference clock per unit of time of the reference clock
    - typically 10^{-6} seconds/second = 1 sec in 11.6 days

Sources of time

- International Atomic Time: based one atomic oscillator: *since 1967 the standrd second has been defined as 9,192,631,770 periods of transition between the two hyperfine levels of the ground state of Causium-133*!!
- Universal Coordinated Time (UTC, from French)
  – based on atomic time but leap seconds inserted to keep in phase with astronomical time (Earth's orbit)
  – UTC signals broadcast every second from radio and satellite stations
    - land station accuracy 0.1-10ms due to atmospheric conditions
- Global Positioning System (GPS)
  – broadcasts UTC
- Receivers for UTC and GPS
  – available commercially
  – used to synchronise local clocks

Clock synchronisation

- External: synchronise with authoritative source of time
  - the absolute value of difference between the clock and the source is bounded above by D at every point in the synchronisation interval
  - time accurate to within D
- Internal: synchronise clocks with each other
  - the absolute value of difference between the clocks is bounded above by D at every point in the synchronisation interval
  - clocks agree to within D (not necessarily accurate time)

Clock compensation

- Assume 2 clocks can each drift at rate R msecs/sec
  - maximum difference 2R msecs/sec
  - must resynchronise every D/2R to agree within D
- Clock correction
  - get UTC and correct software clock
- Problems!
  - what happens if local clock is 5 secs fast and it is set right?
  - timestamped versions of files get confused
  - time must never run backwards!
  - better to scale the value of internal clock in software without changing the clock rate

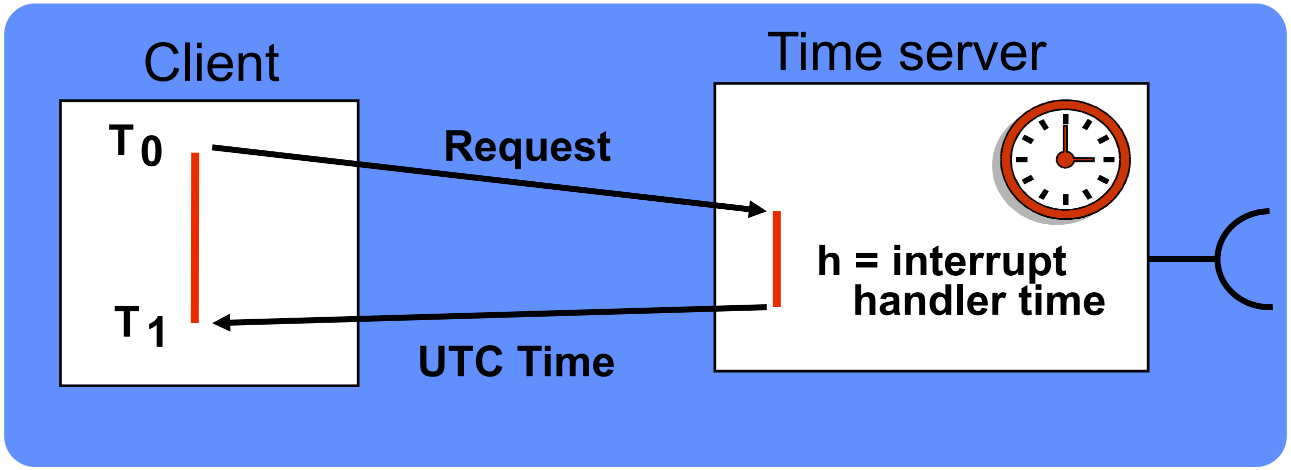
Synchronisation methods

- Synchronous systems
  - simpler, relies on known time bounds on system actions
- Asynchronous systems
  - intranets
    - Cristian's algorithm
    - Berkeley algorithm
  - Internet
    - The Network Time Protocol

Synchronous systems case

- Internal synchronisation between two processes
  - know bounds MIN, MAX on message delay
  - also on clock drift, execution rate
- Assume One sends message to Two with time t
  - Two can set its clock to t + (MAX+MIN)/2 (estimate of time taken to send message)
  - then the skew is at most (MAX-MIN)/2
  - why not t + MIN or t + MAX?
    - maximum skew is larger, could be MAX-MIN

Cristian's algorithm



Time Server with UTC receiver gives accurate current time

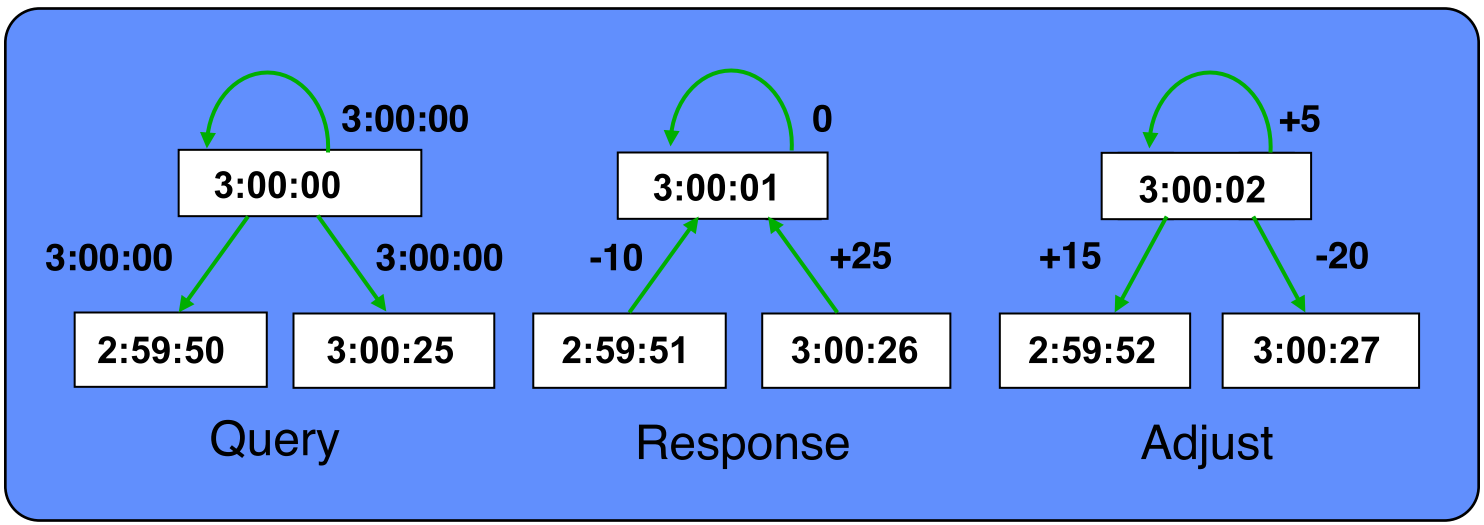
- Estimate message propagation time by $p=(T_1-T_0-h)/2$ (=half of round-trip of request-reply)
- Set clock to UTC+p
- Make multiple requests, at spaced out intervals, measure T_1-T_0
  - but discard any that are over a threshold (could be congestion)
  - or take minimum values as the most accurate

Cristian's algorithm

- Probabilistic behaviour
  – achieves synchronisation only if round-trip short compared to required accuracy
  – high accuracy only for message transmission time close to minimum
- Problems
  – single point of failure and bottleneck
  – could multicast to a group of servers, each with UTC
  – an impostor or faulty server can wreak havoc
    - use authentication
    - agreement protocol for $N > 3f$ clocks, f number of faulty clocks

The Berkeley algorithm

- Choose master co-ordinator which periodically polls slaves
- Master estimates slaves' local time based on round-trip
- Calculates average time of all, ignoring readings with exceptionally large propagation delay or clocks out of synch
- Sends message to each slave indicating clock adjustment



Synchronisation feasible to within 20-25 msec for 15 computers, with drift rate of 2×10^{-5} and max round trip propagation time of 10 msec.

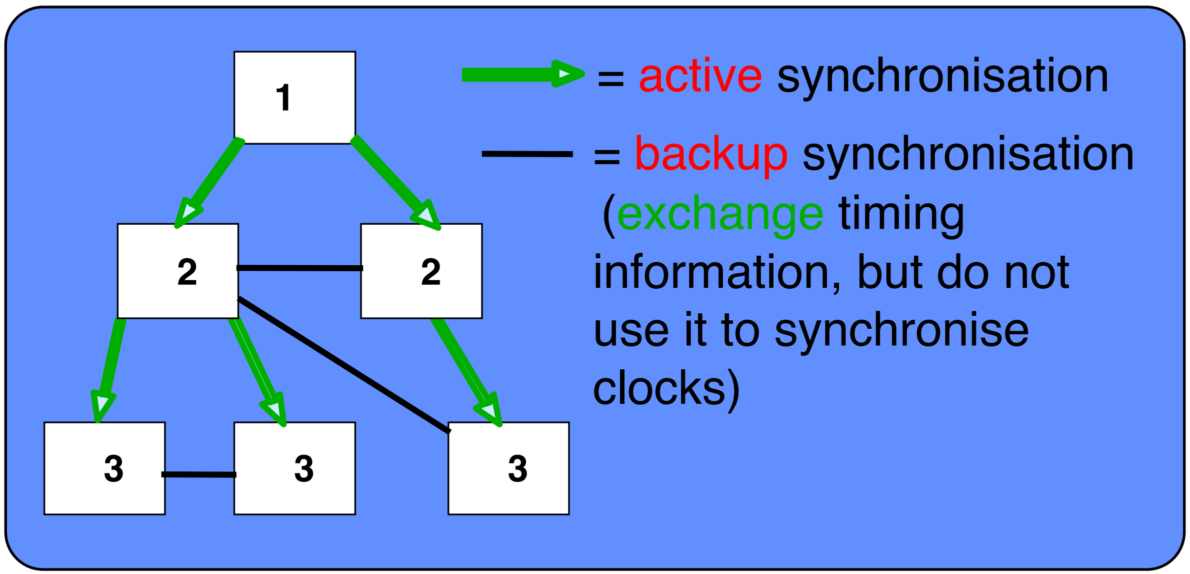
The Berkeley algorithm

- Accuracy
  - depends on the round-trip time
- Fault-tolerant average:
  - eliminates readings of faulty clocks - probabilistically
  - average over the subset of clocks that differ by up to a specified amount
- What if master fails?
  - elect another leader

  How?

Network Time Protocol (NTP)

- Multiple time servers across the Internet
- Primary servers: directly connected to UTC receivers
- Secondary servers: synchronise with primaries
- Tertiary servers: synchronise with secondary, etc
- Scales up to large numbers of servers and clients



Copes with failures of servers – e.g. if primary's UTC source fails it becomes a secondary, or if a secondary cannot reach a primary it finds another one.

Authentication used to check that time comes from trusted sources

NTP Synchronisation Modes

- Multicast
  - one or more servers periodically multicast to other servers on high speed LAN
  - they set clocks assuming small delay
- Procedure Call Mode
  - similar to Cristian's algorithm: client requests time from a few other servers
  - used for higher accuracy or where no multicast
- Symmetric protocol
  - used by master servers on LANs and layers closest to primaries
  - highest accuracy, based on pairwise synchronisation

Logical time

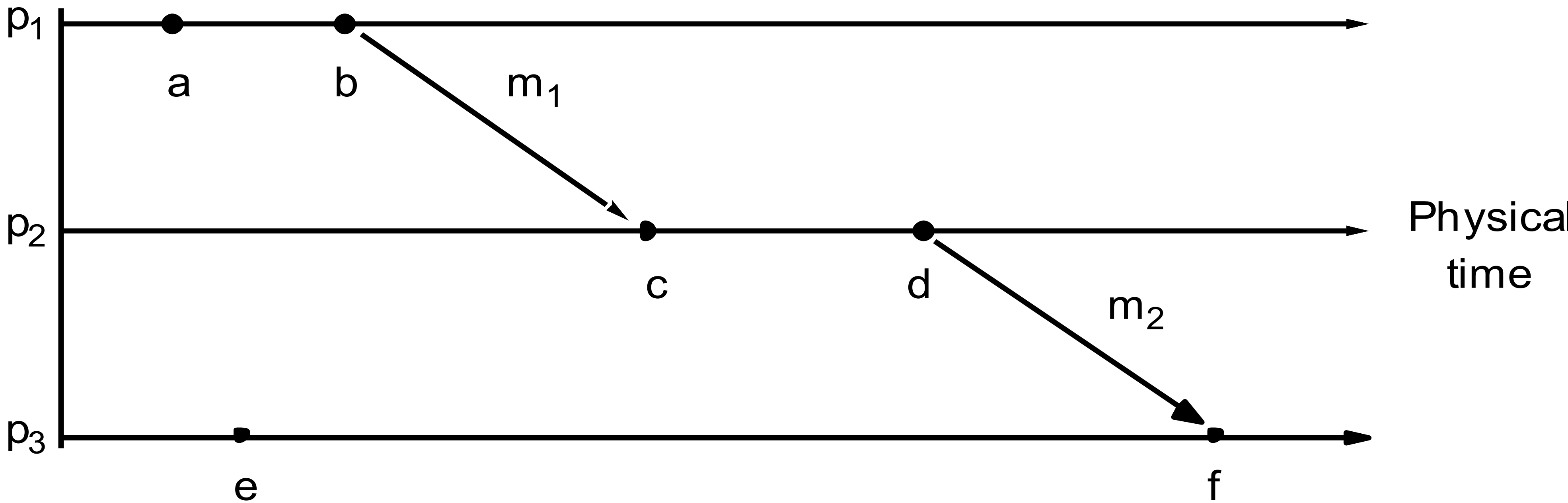
- For many purposes it is sufficient to agree on the same time (e.g. internal consistency) which need not be UTC time
- Can deduce causal event ordering

  a $\rightarrow$ b (a occurs before b)
- Logical time denotes causal relationships
- but the $\rightarrow$ relationship may not reflect real causality, only accidental

Event ordering

- Define a $\rightarrow$ b (a occurs before b) if
  - a and b are events in the same process and a occurs before b, or
  - a is the event of message sent from process A and B is the event of message receipt by process B
- If a $\rightarrow$ b and b $\rightarrow$ c then a $\rightarrow$ c.
- $\rightarrow$ is partial order.
- For events such that neither a $\rightarrow$ b nor b $\rightarrow$ a we say a, b are concurrent, denoted a || b.

Example of causal ordering



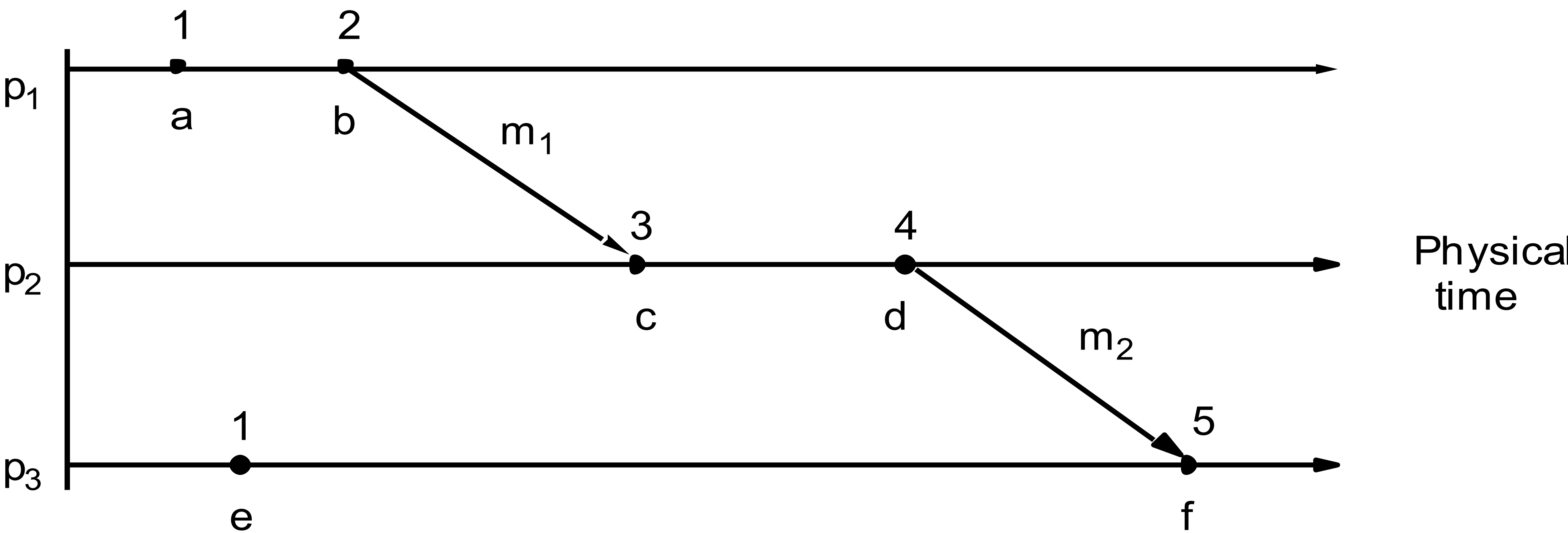
- $a \rightarrow b$, $c \rightarrow d$
- $b \rightarrow c$, $d \rightarrow f$
- $a \parallel e$

Logical clocks [Lamport]

- Logical clock = monotonically increasing software counter (not real time!)
  - one for each process P, used for timestamping
- How it works
  - L_P incremented before assigning a timestamp to an event
  - when P sends message m, P timestamps it with current value t of L_P (after incrementing it), piggybacking t with m
  - on receiving message (m,t), Q sets its own clock L_Q to maximum of L_Q and t, then increments L_Q before timestamping the messa receive event
- Note $a \rightarrow b$ implies $T(a) < T(b)$

What about converse?

Totally ordered logical clocks

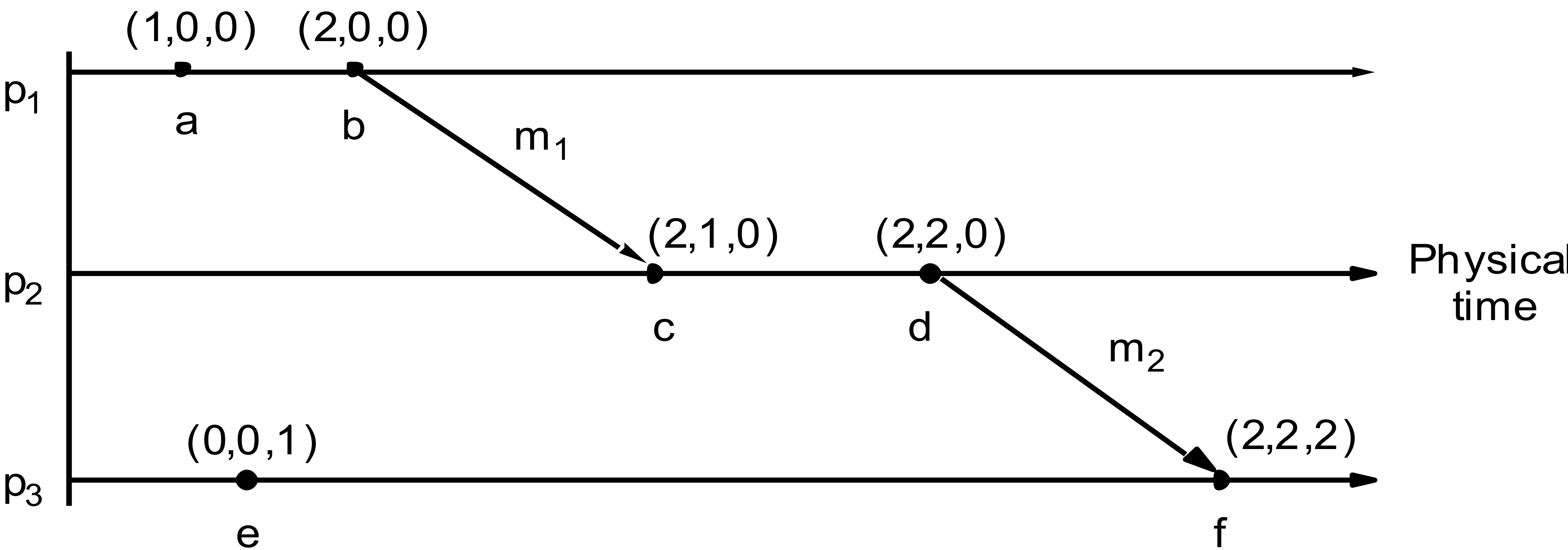


- Problem: T(a) = T(e), and yet a, e distinct.
- Create total order by taking account of process ids.
- Then (T(a),pid) < (T(b),qid) iff T(a) < T(b) or T(a)=T(b) and pid < qid.

Vector clocks

- Totally ordered logical clocks
  - arbitrary event order, depends on order of process ids
  - i.e. (T(a),pid) < (T(b),qid) does not imply a $\rightarrow$ b, see a, e
- Vector clocks
  - array of N logical clocks in each process, if N processes
  - vector timestamps piggybacked on the messages
  - rules for incrementing similar to Lamport's, except
    - processes own component in array modified
    - componentwise maximum and comparison
- Problems
  - storage requirements

Vector timestamps



- VT(b) < VT(c), hence b → c
- neither VT(b) < VT(e), nor VT(b) < VT(e), hence b || e