# Raft as a solution to the consensus problem

#### **Consensus:**

To decide on a common value amongst several processes in a distributed system.

#### **Current solutions:**

Suffer from complex specifications and variations resulting in buggy implementations.

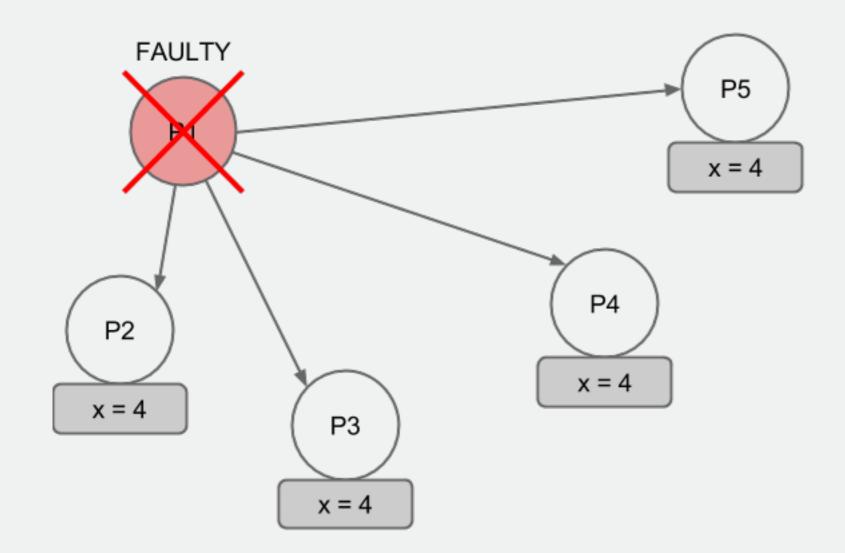
## **Two Generals Problem**

#### Relation to consensus:

Two generals want to agree on when to attack the enemy.

#### **Impossibility:**

The generals will never reach an agreement since they are not sure about the messenger's reliability.



An example of a distributed system containing a faulty leader, which would cause the system to become unavailable.

# **Components of Raft**

#### **Log replication**:

 Commands issued by a user through a client is replicated throughout the system.

#### Leader election:

- A leader is elected to be the link between the client and the rest of the network.
- The leader frequently sends out heart-beat (empty) messages in order to keep track of faulty processes.

#### Safety:

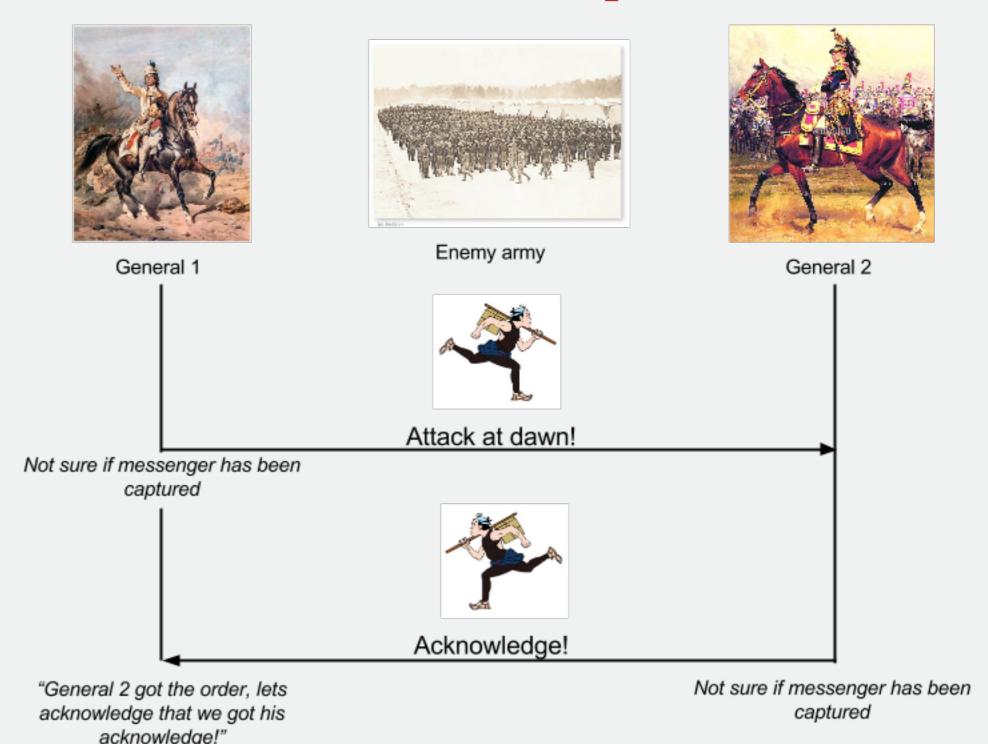
- There can only be at most one leader.
- If a leader crashes a new leader is elected.
- If a faulty process wakes up the leader ensures that their log is updated.

#### Results

- Raft is showcased in an visualised implementation, describing its fault tolerance features in a nice and concise manner.
- The user is able to provide the program with various parameters for testing different heart beat timers, election timeouts etc.

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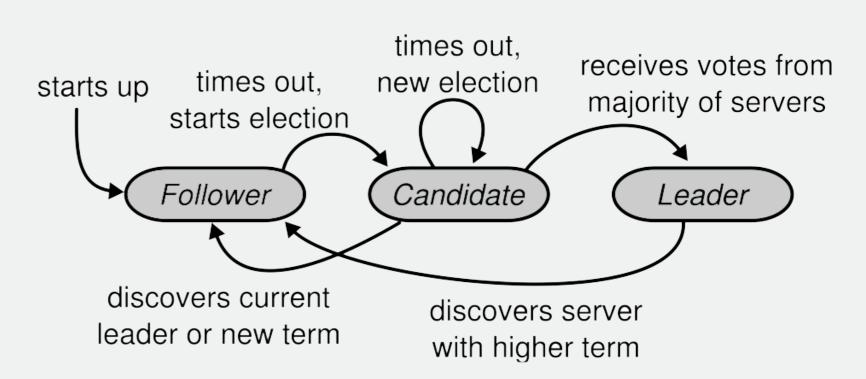
# A fault tolerant and self-repairing system

When you might have found a suitable solution to the consensus problem and implemented it, but you also want it to be fault tolerant.

The Two Generals problem illustrated.

#### What happens when a process fails?

The system should of course still be operational under presence of failure. Solving this requires a fault tolerant consensus algorithm. A new solution to this is <u>Raft!</u>



A state machine showing the state a process can be in.

From the Raft paper - "In Search of an Understandable Consensus Algorithm".

## Test and behavioural driven development

- The algorithm is mainly described by its behaviour without any formal specification or pseudo code.
- From this tests were derived during the implementation. Each test was served as an implementation step.

```
Election timeout: between 4000 and 8000 ms

Heartbeat: every 1000 ms

RPC Delay: between 100 and 200 ms

Server 1 (follower) term: 1 logEntries: 3 commitIndex: 3 4911

[v->X->5, t->1], [v->Y->2, t->1], [v->Z->3, t->1]

Server 2 (follower) term: 1 logEntries: 2 commitIndex: 2 -15101

[v->X->5, t->1], [v->Y->2, t->1]

Server 3 (follower) term: 1 logEntries: 3 commitIndex: 3 3691

[v->X->5, t->1], [v->Y->2, t->1], [v->Z->3, t->1]

Server 4 (follower) term: 1 logEntries: 3 commitIndex: 3 6979

[v->X->5, t->1], [v->Y->2, t->1], [v->Z->3, t->1]

Server 5 (leader) term: 1 logEntries: 3 commitIndex: 3 6681

[v->X->5, t->1], [v->Y->2, t->1], [v->Z->3, t->1]
```