

C++ Declarative API – Implementation Overview Within the XRootD Framework

Robert Poenaru
DFCTI
IFIN-HH
Magurele, Romania
robert.poenaru@protonmail.ch

Michał Simon
Information Technology Department
CERN
Genève, Switzerland
michal.simon@cern.ch

Abstract—A brief description of the XRootD architecture and its purpose within the Worldwide Large Hadron Collider Computing Grid (WLCG), alongside an overview of the server- and client- sides of the XRootD framework are discussed in the present work. The client-side of XRootD has a relatively new feature called Declarative API. Its main objective is to provide the user with an asynchronous interface that is more in line with the modern C++ paradigm. A discussion on the development process for the new API is made, together with a case study that involves the implementation of an Erasure Coding plug-in for the client.

Keywords—XRootD, asynchronous programming, declarative API, pipeline, server, client.

I. INTRODUCTION

Started as a protocol which granted remote access to root format specific files, with a primary use case focused on data analysis (rather than data transfer), XRootD became widely used within the scientific community at CERN (European Organization for Nuclear Research) and other large-scale facilities (e.g., SLAC-Stanford Linear Accelerator Center). Over the last years, the framework evolved a lot, and it now supports data analysis, data transfers, data management, and also features like staging data from tape.

In terms of storage capacity, only the ATLAS and CMS collaborations alone produce a total of around 150 Petabytes of data which needs to be accessed by thousands of physicists within the Worldwide Large Hadron Collider Compute Grid - WLCG community [7]. As a result, a key objective of the WLCG is to assure both the process of moving the data between sites and deliver the data to any end-user application.

The addition of XRootD on top of the Anydata, Anytime, Anywhere project (or AAA for short) [2] allowed the high Energy Physics community to achieve global data storage federations that have a single data-access entry point and also a common data-access protocol, which changed the old paradigm of distributed multi-tiered storage. This is possible through the hierarchical deployment of redirectors that allow real-time discovery of sites that are hosting the data. The XRootD ability to federate different sides through meta managers together with additional functionalities provided by the AAA (like logical file name translation to physical file name) allowed to achieve a global, multi-site environment for data storage and analysis.

To emphasize the importance of XRootD, it is worth mentioning that currently at CERN, the main storage solution is EOS – a technology developed in-house and built on top of the XRootD framework. The LHC experiments (e.g., ATLAS, CMS, LHCb, ALICE) and also other smaller experiments hosted at CERN (e.g., AMS), including their user communities, use EOS for data storage and access.

In terms of its functionality, the XRootD framework is composed of a server-side and a client-side. Each component will be described in detail in the following sections; however, it is worth mentioning that the interaction of any end-user with the XRootD framework (in the process of accessing stored data) will be through the client interface (or shortly XrdCl). Making sure that the stored data from any of the facilities which run experiments is available to the user and assuring a constant transfer bandwidth even when the distributed storage system is accessed by a multitude of clients represent a real challenge, especially when considering that, as in any kind of data storage facility, equipment may fail (for example disks that stop working could lead to entire storage blocks to be unresponsive). Nowadays, with the larger capacity disk drivers, when one disk fails it can take days to rebuild data and restore processes. Not having access to the desired data or even losing it completely proves to be the worst-case scenario for the entire community (for both the service providers and the end-user). As a result, in the case of large data centers, a crucial aspect is the efficient repair of failed (storage) nodes and the reliability of the data. Both can be ensured by introducing redundancy (e.g., ranging from straightforward replication to the use of complex schemes that minimize the storage overhead while maximizing the reliability). A very efficient method that aims at such a thing is the so-called Erasure Coding (EC) scheme. It is important to understand that EC started to gain significant interest in the design of storage systems that offer low (minimal) overhead and minimize the repair times of faulty storage nodes.

Implementing an Erasure Coding mechanism within the XRootD framework would represent a great accomplishment for the scientific community at CERN. The present work aims at showing the development steps of such a tool, by describing how a plug-in mechanism that improves the data redundancy and reliability is created. Moreover, the workflow is chosen in such a way that code efficiency and optimization are the priorities - using a so-called Declarative API (a new feature of the XRootD client). The adopted approach will be compared with an existing API, and arguments on why the former method is more efficient will be presented.

In the following section, we provide a clearer picture of the XRootD framework, both in terms of its server-side as well as its client-side, since both implementations are crucial in understanding the overall workflow of data access and data manipulation within the WLCG community. Furthermore, a description of the event-loop mechanism will be given, together with an overview of the asynchronous API of the XRootD client. A section dedicated to the Erasure Coding mechanism will be made as well, with the adoption of the C++ Declarative API as development tool for creating such a plug-in in the client. Finally, a comparison between the developed plug-in (using Declarative API) and an existing asynchronous

API is shown, with some arguments on why the new API is more efficient.

II. XROOTD FRAMEWORK

The main objective of any scientific project that is based on experiments that ran at CERN (but also to the other places within WLCG) is the access to the computing resources which are used for submitting jobs that aim to solve a particular task. An old model of such a workflow is described in Fig.1 (also called “jobs go to data” paradigm [2]).

Whenever the user wants a local copy of the data that is studied, a change of workflow must be made from using the data analysis tools to the usage of data transfer toolset (which is usually provided by the experiment’s computing facility or the grid middleware [2]). This introduces significant overhead and as a result, slows down the process of tackling the actual tasks which have to be performed by the physicists with the required data. A Federated storage system is the implementation that aims at solving such issues. Defined in [2] as a collection of unpaired storage resources that are managed by a set of domains that are cooperating (but also independent) and also are accessible via a common namespace. By using multiple dedicated XRootD servers at each site and a centralized redirector (an in-depth description of an XRootD redirector can be found in [2]), it is possible to build these storage spaces where the user makes direct contact with the central endpoint and is redirected to a site which can provide the necessary data.

A. Server-side XRootD

At its core, XRootD acts like any remote data server, however, it does seem innovative in terms of its scalability, robustness, fault tolerance, job recovery (in case of job failing during an execution), cache mechanism, and many more. A tremendous work (progress) has been done in recent years, especially for extending the scalability features (e.g., [1], [8]), caching [2], and many more. The development team is constantly committing new or improved features, and these are documented on the official repository [10]. Other characteristics of an XRootD server that assure a high-performance data availability are load-balancing, optimal use of hardware resources (like sockets, memory, CPU), cooperation between different (XRootD) servers, minimize

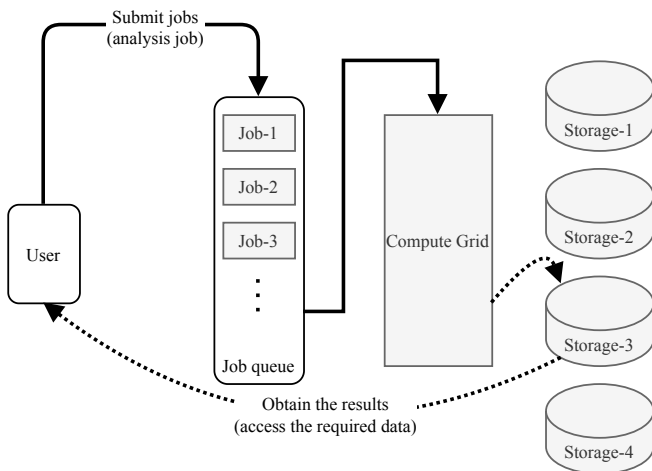


Fig. 2. Process of accessing data in the “jobs go to data” mode. User submits an analysis job that is sent through the compute grid to the sites that host the data.

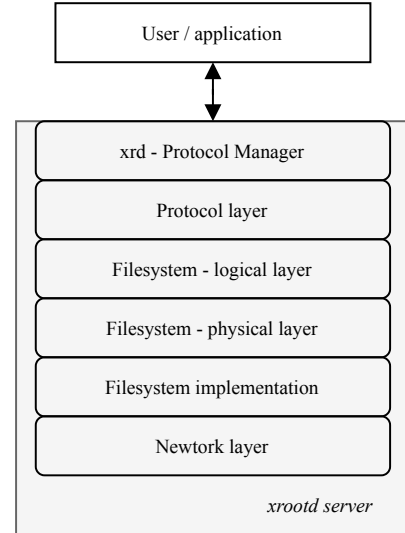


Fig. 1. XRootD server architecture.

the number of jobs that have to be restarted due to a server or network problem.

The XRootD server architecture is composed of four main layers, namely: Network layer, Protocol layer, File-system layer, and a Storage layer (see Fig. 2). Being developed on a run-time plug-in mechanism, new features can be added to the framework with little effort. The main reasons for developing the XRootD within a layered model are the optimization of specific functionalities while minimizing resource usage and isolation of services allows for dynamical loading (determining in this way which implementation works best in a particular environment [1]).

III. THE XRDCL IMPLEMENTATION

The XrdCl implementation developed within a multi-threaded C++ paradigm within the XRootD client and it is based on a concept called event-loop [6]. XrdCl is provided by the *libXrdCl* library which is part of the client source code [10]. The entire C++ API for the XRootD framework is available on the official documentation page [11] – provided by the development team.

A fully asynchronous implementation is available for XrdCl (each asynchronous call has been implemented into the corresponding synchronous version of it). This is a great achievement for the XRootD framework, as having asynchronous behavior of the function calls for requesting/service data access to users greatly improves performance (however, at the cost of a slight increase in code complexity).

All the requests submitted by the user within the application are queued and then executed by the socket event-loop. This execution of requests is done in a single-threaded manner – sequentially – although there is a possibility to increase performance by upping the number of event-loops. On the other hand, all of the incoming responses are processed by the event-loop, but the response handlers are executed in a so-called thread-pool [6]. XrdCl is flexible, meaning that it can be configured using a configuration file with environment variables or directly from the C++ API.

A. The event-loop in XRootD

A user might want to retrieve some data using the XRootD client from a file that is located on a server. Interaction between the XRootD client and that particular server is done over TCP protocol. Using the *epoll* system call, the XRootD client runtime receives events from the kernel signaling whether there is available space in the TCP-output buffer for writing data (i.e., requests which will be sent to the server) or if there is some data in the TCP-receive buffer for reading responses from the server. In this event-based workflow, there is a queue of requests that the client is issuing to the server, and with each write-event, a request is removed from the queue and it is being written on the socket. It is worth mentioning that the TCP buffers (for both sending and receiving data) might not have enough size to allow requests/responses to be written/read in a single event, meaning that it can take several write/read events to process an entire request to the server or a response from the server. Furthermore, each request has a corresponding message handler, so that after a request is written to the socket (in order to be sent to the server), the accompanying message handler is moved into a queue for incoming responses. During a read-event yielded by the event-loop, the client is informed that it can readout from the socket the server response. Once a response arrived from the server, its corresponding message handler (located inside the incoming queue) is also taken out from the queue, and finally, after the response is parsed, the callback function is being called. In terms of processing stages, the event-loop generates the following events: *ready-to-read*, *ready-to-write*, *read-timeout*, and *write-timeout*. According to each of the event types, the client is sending requests, is receiving responses, and handling timeouts. Fig. 4 aims to give a schematic representation of the entire workflow.

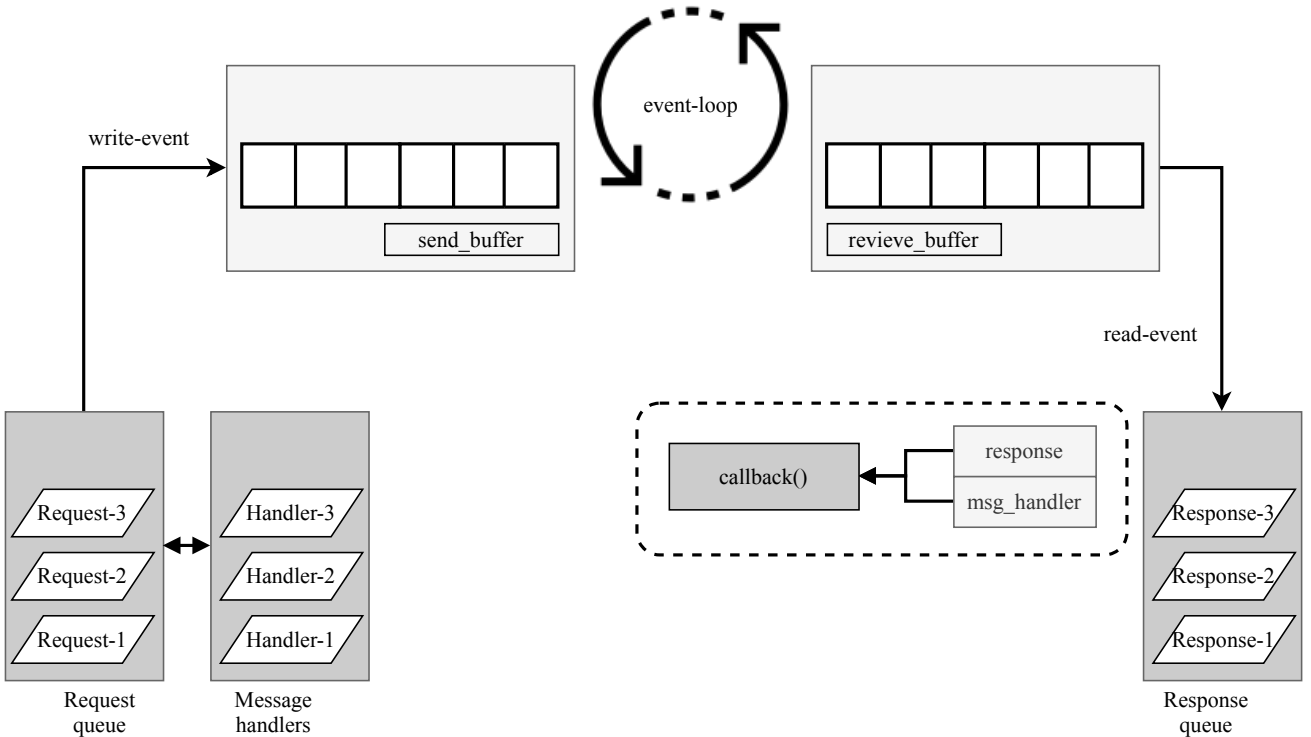


Fig. 4. The event-loop in XRootD.

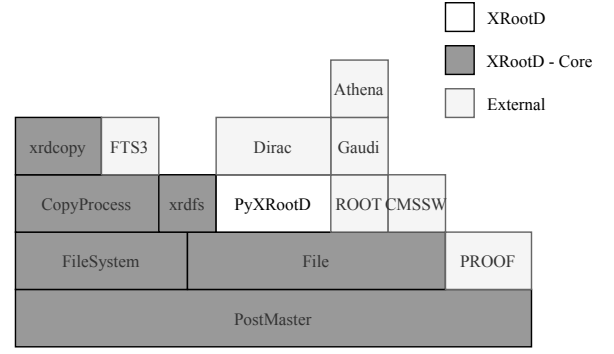


Fig. 3. Structure of the XrdCl API stack.

XrdCl hides any of the low-level connection handling from the user. The workflow of an application starts with a request which is issued as a connection between the client and the server. Once the connection has been automatically established, it will be kept alive for further usage, until the time-to-live timeout elapses. The XrdCl implementation is routing all the requests through a single (physical) connection, although, it is possible to force the component to use up to 16 simultaneous physical connections, improving in this way the performance over a network of WAN type. Disconnection of the client from a server can be forced, depending on the actual needs; for example, the user might want to re-establish the connection with new credentials. In fact, the client authenticates (on server request) during the XRootD handshake that happens when the connection is being established.

The entire XrdCl API stack is represented as a block diagram in Fig. 3, where each of the components is organized in three main categories: XRootD-Core, XRootD, and External.

Since only the File and FileSystem objects within the XrdCl stack are part of the focus within the current work, it

is worth mentioning some key characteristics of these implementations.

The XrdCl library is the foundation part of the following components of the XRootD client:

- The command-line interface [6].
- Python bindings: designed to facilitate the usage of the XRootD client, by writing Python instead of having to write C++ [9].
- SSI Client: a multi-threaded XRootD plug-in that implements a request-response framework [12].
- The POSIX API.
- New: C++ Declarative Client API (with release of XRootD v.4.9.0).

B. Asynchronous implementations within XRootD client interface

The fact that XRootD is mainly used with file-based data repositories, a crucial component is indeed the file access API. It was already mentioned that these objects have both synchronous and asynchronous behavior. What this means from an API standpoint is that the asynchronous functions within File and FileSystem objects take one extra argument: the so-called handler objects (see Listings 1 and 2 for the core difference).

```
XRootDStatus File::Open(const std::string &url,
                        OpenFlags::Flags flags,
                        Access::Mode mode,
                        ResponseHandler *handler,
                        uint16_t timeout)
```

Listing 1: Asynchronous version of the Open method.

```
XRootDStatus File::Open(const std::string &url,
                        OpenFlags::Flags flags,
                        Access::Mode mode,
                        uint16_t timeout)
```

Listing 2: Synchronous version of the Open method.

The handler object implements specific interfaces, and its methods are called whenever the response from the asynchronous function call arrives. An example for such a response handler object is given in the Listing 3.

```
class Handler: public ResponseHandler
{
public:
    void HandleResponse( XRootDStatus *status,
                        AnyObject *response)
    {
        Response *res=GetResponse<Response>(status,
                                             response);

        //Perform operations using the response object

        delete status;
        delete response;
        delete this;
    }
}
```

Listing 3: An example with a handler class implementation.

Whenever the client uses the asynchronous function, it is called within the call stack and ran in the background. This means that the program does not have to wait for the function

execution (asynchronous calls => non-blocking operations). In case the user wishes to use only asynchronous operations, the subsequent operation needs to be called from the handler of the previous operation.

A usual execution flow that involves file operations might consist of a function that tries to open the file (e.g., Open). Its response handler must call the second operation (e.g., Read, Write) that needs to be called. The second function has a handler as well, which will eventually call the third operation (usually the closing operation on that specific file which the client has accessed; Close). It is also worth mentioning that each operation call requires different arguments and as a result, each handler will have its corresponding implementation. It is relatively easy to see that even a simple flow requires some serious amount of work, and this will scale up with each function that the client has to execute.

The asynchronous API can become quite cumbersome, especially in terms of code readability. In order to emphasize this, in Listing 4 an example is shown. Within that snippet, the first operation call is the Open method, while further execution of the flow of operations will take place in the handler. The user must go through an entire set of handlers, which could be time consuming and inconvenient.

```
const string path = "/path/to/testFile.dat";
const OpenFlags::Flags flags = OpenFlags::Read;
const Access::Mode mode = Access::None;

auto openHandler = new CustomOpenHandler();
File *file = new File();

file->Open(path, flags, mode, openHandler);
// Further execution in handler: Read->Close
```

Listing 4: Asynchronous implementation for reading a file within XrdCl.

Fortunately, a newly introduced implementation within the XrdCl framework aims at simplifying an asynchronous operation pipeline: Client Declarative API [6]. This new feature will be discussed in the following section.

IV. THE CLIENT DECLARATIVE API

Introduced in version 4.9.0 of the XRootD package, the Declarative API [6] was designed and implemented to facilitate the usage of XrdCl API by the users. It has been built on top of the existing API and provides an additional layer of abstraction (that layer itself is what makes a more convenient interface between the client and the end-user). This section is dedicated to describing the main parts and characteristics of the implementation.

Its key features that make the API easy to use are the following:

- Define an entire operation workflow in a contained space, without the need of fragmenting the logic into many classes and implementations.
- The syntax is declarative-centric, meaning that users should focus on the actual choice of operation rather than paying much attention (effort) to the execution flow.
- Proper signaling for the user of any incorrect declarations and configurations during the compilation phase.
- Error handling for the workflow is done consistently, showing proper error messages within the same space where the workflow is done.

The proposed API provides a syntax for chaining consecutive operations: the result of one operation is used to compute the following operation, making this implementation very robust. Listing 5 shows an example of operations workflow using the Declarative approach. One can see that the new API is more in line with the modern C++ language paradigm.

```
File *file = new File();

auto readHandler = new ResponseHandler();

// open, read from and close the file
auto &pipeline= Open(file)(path, flags, mode)
    | Read( file )(offset , size ,
        buffer) >> readHandler
    | Close( file ) ( ) ;

auto status = WaitFor(p);
```

Listing 5: Declarative syntax within XrdCl.

From Listing 5, one can see that the flow of file operations is assigned to a pipeline variable. For each operation (namely Open, Read, and Close) the corresponding object is created, and the operator () is used for passing arguments to the operations. The operation itself dictates the number of arguments and their types. A handler is introduced after the second operation through the >> operator, although this is optional, as the operation handler is not controlling the flow anymore. The example shown in Listing 5 only has only one handler, that is for the Read function; the last line contains a utility for synchronous execution of the pipeline (current thread waits until the entire pipeline chain of operations is finished). The defined operations are chained to each other by the | operator. It is worth mentioning that all these implementations added within the Declarative API are possible because of the operator overloading feature of the C++ programming language.

The syntax also supports parallel execution of multiple flows of operations (XrdCl::Parallel implementation is part of the Operation Utilities within the Declarative API toolset). The Parallel utility aggregates several operations (those might be compound operations) for parallel execution. It also accepts a variable number of operations. An example pipeline with three parallel operations can be seen in Listing 6. Even more so, it is possible to have pipelines run in parallel. Such an example is shown in Listing 7.

```
auto &o1 = Open(file1,path1,OpenFlags::Read);
auto &o2 = Open(file2,path2,OpenFlags::Read);
auto &o3 = Open(file3,path3,OpenFlags::Read);

// open 3 files in parallel
Pipeline p = Parallel(o1,o2,o3);

auto status = WaitFor( p );
```

Listing 6: Parallel operations in XrdCl. Execution of multiple functions.

A. Pipeline semantics

In order to emphasize the overall flexibility of the pipeline syntax, the following example is proposed: the user wants to access a file with a size of 0.5MB from a data batch on a server. Using the declarative approach, the procedure will

```
auto &pipe1 = Open(file1)(path1,flags)
    | Read(file1)(offset,size,buffer1)
    | Close(file1)();

auto &pipe2 = Open(file2)(path2,flags)
    | Read(file2)(offset,size,buffer2)
    | Close(file2)();

auto &pipe = Open(lockFile)(lockFileURL,flags)
    | Parallel{&firstPipe,&secondPipe}
    | Close(lockFile)();

auto runPipes = WaitFor( pipe );
```

Listing 7: Parallel operations in XrdCl. Execution of multiple pipelines.

look like Listing 8. The first line is for the declaration of a lock file, then the lock file is created with the first call of the Open function. Once the lock file has been created, the pipeline continues by doing an open, a read, and a close for the actual file that needs to be accessed. The Rm() function is used for deleting the lock file since it is not needed anymore.

What is important to note is that if an operation fails to complete execution, any subsequent operations within that pipeline will not be executed, but their handlers will be called (with error status). Using the pipelining semantic makes the control flow clearer and more robust.

```
File lock, file;
FileSystem fs(url);
std::future<ChunkInfo> resp; // server response

auto &p = Open(lock,"root://host//path/to/.lock",
    OpenFlags::New)
    | Close(lock)
    | Open(file, "root://host//path/to/file.txt",
    OpenFlags::Read)
    | Read(file,0,512,buffer) >> resp
    | Close(file);
    | Rm(fs, "root://host//path/to/.lock");

// wait for the pipeline to complete
auto status = WaitFor( p );
```

Listing 8: The pipeline semantic in XrdCl.

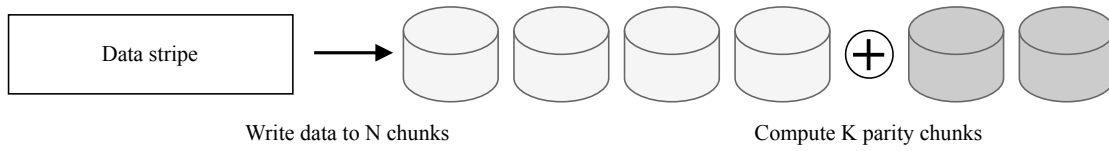


Fig. 5. Erasure coding: decode scheme, with $N=4$ chunks and $K=2$ parity chunks.

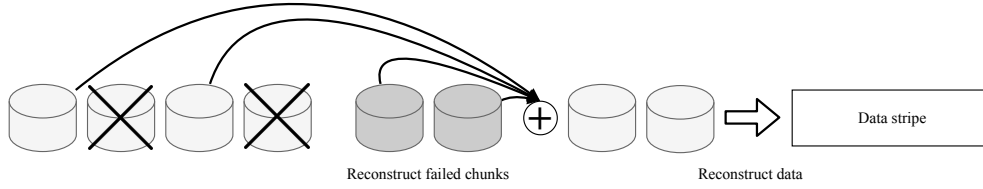


Fig. 6. Erasure coding: encode scheme, with 2 failures in the storage grid.

B. Implementation of a plug-in for the XRootD client using Declarative API

The main use case for the declarative API is the development of an erasure coding plugin for the client. Erasure Coding (EC) is a method of data protection in which data is broken into fragments, expanded and encoded with redundant data pieces, and stored across a set of different locations or storage media. Its importance within the XRootD framework was discussed in the introduction of this work.

The goal of erasure coding is to enable data that becomes corrupted at some point in the disk storage process to be reconstructed by using information about the data that's stored elsewhere in the array. The tradeoff for erasure coding is that it can be more CPU-intensive, and that error recovery might result in increased network traffic and latency. EC encodes N chunks of data (of equal size) in such a way that the result is the N original data chunks and additional K chunks of parity ($N+K$ chunks in total). Every N chunks of the obtained $N+K$ chunks are sufficient to recover the original N chunks. The data protection scheme is graphically represented in Figs. 5 and 6, where the decode and encode procedures, respectively, are explained.

Developing the EC procedure will imply that an entire block of data will be stripped into N data chunks and K parity chunks. One needs to open all stripes, write to all stripes, set extended attributes on all stripes (e.g., checksums), then finally close all stripes. For efficiency, the write operation and setting extended attributes should be done in parallel.

In order to understand why the Declarative API simplifies the workflow, it is worth mentioning how the standard XrdCl asynchronous API would manage the entire EC pipeline. The standard asynchronous API is the alternative approach which

one could take as a development process instead of the Declarative API, but it turns out that such an approach would result in a less optimal workflow, with a much higher code complexity.

In the standard asynchronous API, to update a single chunk of data, one would have to write a function that opens, writes, sets extended attributes, and closes a file asynchronously. However, the write procedure (together with the following chain of operations) will be hidden in the callback of the handler corresponding to the `Open()` function. Furthermore, writing to the file, setting extended attributes, and closing the file would each have a handler that is taking care of the execution process. Keep in mind that this entire workflow is only for one chunk, and the functions for writing and setting extended attributes execute sequentially. One would need a handler-class to aggregate these procedures in a parallel execution. Updating the data stripes and parity stripes will also require a handler class in order to have a parallel execution. This entire workflow induces a lot of boilerplate for the user (when creating the required flow of operations), and it makes a repetitive process (by requiring handlers and handler-class construction when trying to execute in parallel). A clear workflow is hidden from the user, since the callbacks are embedded into the first handler operation: one needs to go through the entire set of handlers in order to understand the full execution pipeline. This is depicted in Listing 9, where the `Open()` procedure is written using the (standard) asynchronous codebase. The fact that the write procedure (and additional steps) is embedded in the callback of the `Open` function is mentioned as comments inside the listing. Moreover, each operation call requires different arguments, so each handler needs to have different implementation, meaning that one needs to declare a handler class for each handler separately (i.e., a class for opening a

```
void ECWrite(uint64_t offset,
            uint32_t size,
            const void *buffer,
            ResponseHandler *userHandler)
{
    //arguments must be translated to chunk specific parameters
    File *file = new File();
    OpenHandler *handler =
        new OpenHandler(file, userHandler, /*arguments*);
    //the above operation is in fact writing to the file
    //however, only the Open call can be seen, since all the logic is hidden in the callback
    // --- > unclear workflow
```

Listing 9: The first operation required in the development of `ECWrite`, using the standard asynchronous API.

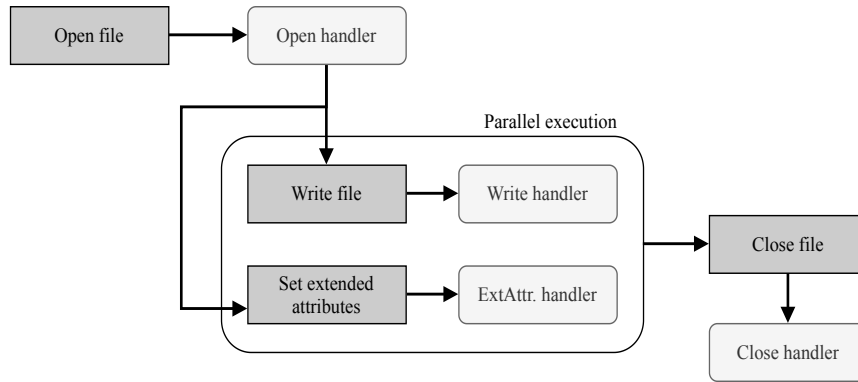


Fig. 7. The flow of operations to be executed when the client starts an Erasure Coding procedure.

file, class for writing to the file, setting special attributes and finally a class for closing the file). Within each handler, the operation status needs to be checked for potential errors, and then the occurring errors must be handled properly. For complexity reasons, the other operations involved in the plug-in are neglected in terms of code-listings. Nevertheless, one can easily see that writing and implementing the entire logic using this approach will induce a high degree of code complexity, making the overall workflow hard to follow (with repetitive code and lot of code-boilerplate).

On the other hand, using the Declarative API, the amount of code boilerplate is significantly reduced when comparing the standard asynchronous operation. The obtained code is much more readable, with a clear workflow and reduced complexity. In the contrary, as mentioned, the standard asynchronous operations hide the actual workflow of operations behind the first function callback (e.g. in the Open->Read->Close pipeline, the entire workflow is hidden in the callback of the Open() function). Fig. 7 describes the entire flow of operations (including the parallel execution of the write to each chunk and setting extended attributes).

Listing 10 contains the necessary workflow, reduced to a straightforward execution pipeline (around 20 lines of code

for a parallel process which runs asynchronously). The pipeline variable contains the composition of operations (constructed with the pipe “|” operator). Within this procedure, the parallel execution of operations is also constructed with the Parallel() function, with the arguments that write and set attributes to each data chunk. All the operations are finally executed asynchronously, with the callbacks marked by the stream operator “>>”.

With the new API, it was possible to implement Erasure Coding successfully for the XRootD framework, keeping a clear codebase, which is also consistent with the modern C++ paradigm). Due to a higher degree of code complexity involved in the standard (pre-existing) API, the Declarative API was proven to be the more optimal approach.

V. CONCLUSIONS

In the present work, a detailed overview of the XRootD framework was given, together with its major importance within the WLCG group and the High Energy Physics community. Along that – also in the introduction - the importance of data redundancy and reliability in a storage facility was discussed, with the Erasure Coding mechanism as a tool for these key aspects (having thus EC as a motivation

```

//Erasure Coding
void ECWrite(uint64_t offset,
             uint32_t size,
             const void *buffer,
             ResponseHandler *userHandler)
{
    /*** start of workflow ***/
    std::vector<Pipeline> writes;
    writes.reserve(n_chunks);

    for(size_t id=0;id<n_chunks;++id)
    {
        //compute offset, size and buffer for each stripe/chunk
        File *file=new File();
        Pipeline p=Open(file, url, flags)
            | Parallel(Write(file, chunk_offset, chunk_size,chunk_buffer)),
              SetXAttr(file, "xrdec.chksum",checksum))
            | Close(file) >> [file] (XRootDStatus &){delete file;};
    }
    /*** end of workflow ***/

    //execute the workflow asynchronously
    Async(Parallel(writes)>>
        [userHandler] (XRootDStatus &status)
        {userHandler -> HandleResponse(new XRootDStatus(status),0);});
}

```

Listing 10: Implementation of the Erasure Coding plug-in with Declarative API.

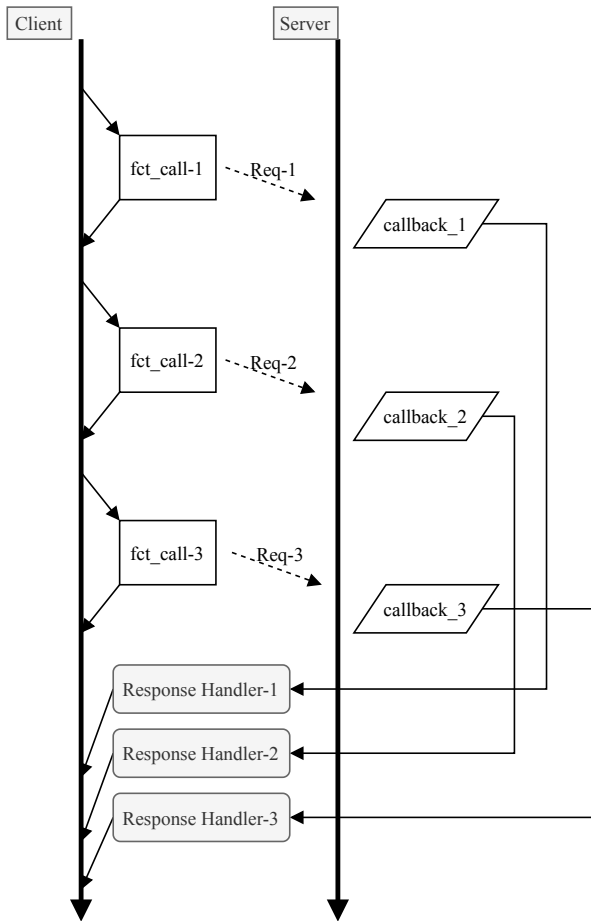


Fig. A1: Asynchronous workflow in terms of response handlers.

for the practical part of this study). Furthermore, a short description of the architecture for both the server-side as well as the client-side was discussed. The asynchronous behavior of the XrdCl API which is written in C++ has been reviewed, with the latest features and release (a special focus was given on the File and FileSystem objects within the XRootD client). The standard asynchronous API importance in terms of usage has been mentioned and also the drawbacks in terms of code complexity. Subsequently, a discussion was made on the Declarative API, which is built on top of the existing XrdCl asynchronous API, with its main feature being the ease of use from a code-logistic standpoint. The Declarative API was adopted in the implementation of an Erasure Coding plug-in inside the XRootD client. It is showed that Declarative API is an efficient tool in providing an asynchronous C++ interface for the user while keeping a clear and concise workflow – drawbacks of the standard asynchronous API being presented in section IV-B. It is concluded that the new API seems to be a suitable tool for developing plug-in tools for the client in an efficient way, without the drawbacks of the standard API.

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APPENDIX

The asynchronous workflow for a chain of operations was discussed in Section III. The diagram in Fig. A1 aims at giving a schematic representation of the pipeline, including the concept of response handler.

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