

# 1. Utilizing Kubernetes as an universal control plane

## 2. Abstract

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## 4. Dictionary and abbreviations

- IaC = Infrastructure as Code
- CaC? [\[source\]](#)
- GitOps = Operations configured by code checked into git
- CNCF = Cloud Native Computing Foundation
- Cloud Native = Cloud provider agnostic technology. E.g Kubernetes and all other projects handled by the CNCF.
- Control plane = The concept of a service watching a configuration and controlling some state or system. A example of this is Kubernetes' internal control plan that schedules pods/containers based on a declared state.
- GCP = Google Cloud Platform
- AWS = Amazon Web Services
- Kubernetes operator = ...

## 5. Introduction

With the invention of Kubernetes we are seeing a rise in popularity of Control Planes. The Concept is built on the idea that you declare a state and services then watches the state and make sure that system actual state reflects the state declared. If the desired state changes, the control plane ensures that the new state is automaticity reflected in the actual state. Control planes are self-healing and they automatically correct drift.

Kubernetes is er perfect eco-system fundament for Control Planes because most things inside is controlled by control planes. At is core Kubernetes stores a state declared in YAML and different services watch this state and make sure the actual state reflects the declared state. Kubernetes can easily be extended by creating new services that watches the state and acts accordingly. During the last years, new control planes have emerged that also manage external resources. It works more or less the same way, but now the services instead insure that some external state correspond to declared

Now the question is if we can combine these tools in order to create a universal control plane for handling all kinds of states, all managed from within Kubernetes. How would such a setup look? How would you interact with it? And what concerns and implications may such a setup bring?

This paper is written in collaboration with Eficode. Eficode is a consultant company that specializes in DevOps. Eficode helps companies support or transform their DevOps processes. Eficode is always interested in keeping up with the latest trends and technologies in DevOps, so they can give their customers the best advice.

Eficode has already written about how Terraform does not scale well for big organisation is their post: [Outgrowing Terraform and adopting control planes](#).

Terraform has proven to be a stable and reliable infrastructure tool for many years now, but it may not always be the best solution. New technologies get showcased, and new paradigms emerge.

In order to recommend costumers to transition infrastructure managed by control planes instead of tools like Terraform, it is essentials to know the implications of such changes, and what kind of challenges such a change might bring. This paper will implement a universal control plane for handling both custom software and cloud resources, and discuss the implications.

The design and implementation presented in this Paper is done by myself, and Eficode has not been part of it.

## 5.1. Control planes

Control Planes is a new paradigm in the realm of DevOps and infrastructure management.

Many of the technologies leveraging the concept of control planes are still considered new and do not have many years of proven use. Even though many of the tools/systems look promising, it can be difficult to justify the investment in transitioning a DevOps infrastructure to this new paradigm.

Control planes is based on so called `Reconciler` pattern . If a service follows the Reconciler pattern it is based on the idea checking the difference between the desired state and the current state and if there is a deviation, a it tries to take action to make the current state reflect the desired state.

## 5.2. Declarative vs Imperative

If we want to build a universal control plane for handling all our infrastructure we need to base it on some core design ideas. First of all we need to want to build our infrastructure as Infrastructure as Code (IaC) using as much declarative configuration as possible. We want to limit the amount of imperatives commands and long script of sequential steps as much as possible.

Declarative and Imperative is two different DevOps Paradigms. Declarative Programming specifies *what* final state we want, while imperative programming specifies *how* we want to get to a given state.

We see this paradigm all across software development, from CSS in web development [\[source\]](#) to Terraform in infrastructure management.

The imperative setup scales poorly in large software environments. "While using an imperative paradigm, the user is responsible for defining exact steps which are necessary to achieve the end goal, such as instructions for software installation, configuration, database creation". The developer has to carefully plan every step and the sequence in which they are executed. Suppose a change in the setup has to be made. In that case, the developer has to carefully make sure the change doesn't break something else in the sequence of steps - especially if there is conditional-statements, meaning there is multiple possible paths through the sequence of steps. Although suitable for small deployments, imperative DevOps does not scale and fails while deploying big software environments, such as OpenStack" [\[source\]](#)

Creating a declarative configuration is a higher abstraction than declaring a configuration with sequential imperative steps. Every declarative API encapsulates an imperative API underneath. For an declarative API work, there needs to be some code behind the scenes that parses the files and acts upon them in an imperative way. Declarative programming can not stand alone because there will always be a sequence of imperative steps executing some operations on a machine in. [\[source\]](#) and [\[source\]](#).

## 5.2.1. Terraform

A very popular tool that is based on the idea of IaC and declarative configuration is Terraform. Terraforms popularity started in 2016-2017 and has been going strong ever since. Now Terraform has integration with more than 1700 providers [\[source\]](#). So the natural question is now why bother with control planes when tools like Terraform exists? This section will describe some of the issues related to using Terraform and why it might be better to use control planes for handling external resources.

"HashiCorp Terraform is an infrastructure as code tool that lets you define both cloud and on-prem resources in human-readable configuration files that you can version, reuse, and share. You can then use a consistent workflow to provision and manage all of your infrastructure throughout its lifecycle. Terraform can manage low-level components like compute, storage, and networking resources, as well as high-level components like DNS entries and SaaS features."

"Terraform creates and manages resources on cloud platforms and other services through their application programming interfaces (APIs). Providers enable Terraform to work with virtually any platform or service with an accessible API." - HashiCorp [\[source\]](#).

### 5.2.1.1. Barrier of entry

The only practical way of using Terraform in teams is to store the state in some remote place. This is commonly done on a cloud provider in some kind of "bucket"/"blobstorage". Setting this up can be a big hurdle to overcome if you have not done it before and you are not an experienced developer. So before you can solve *whatever your code is supposed to solve*, you first need to solve the problem of *how and where to store the Terraform state*, before you can even start developing anything in your team.

Removing this step by switching to control planes is a selling point on its own. Lowering the amount it takes to start up projects is always a good thing.

### 5.2.1.2. Challenges with managing state

If you are distributed team it is a must to store the Terraform state in some remote place. But just because it is shared in a remote place does not mean two people can work on it at the same time.

When storing the state in a remote place, you need to specify a so-called `backend`, but not all `backend`s support locking. This means that in some cases, race conditions can still happen (if two people run `terraform apply` at the same time) since there is no lock on the state. An example of this is that there is no lock on the state if stored on AWS S3. A solution to this is to store lock file somewhere else (e.g. AWS DynamoDB) [\[source\]](#). This, again just adds to the complexity and works an even bigger barrier if you want to make sure your Terraform is safe to use.

Furthermore, if a `terraform apply` goes wrong because the process is interrupted for whatever reason, the state can end up not being unlocked, and you have to `force-unlock` the state [\[source\]](#). This is, of course, a nice feature to solve the issue - but the main problem here is that this can happen to begin with.

Things can get even worse if a `force-unlock` is executed while another process is in the middle of applying [\[source\]](#). Managing mutual state in a distributed state is difficult at its core.

But even though there may be a lock that makes sure that there is no race condition while applying, only one person can work on the state at once. Updating a Terraform state can take minutes - e.g., it will take around 10 minutes to spin up a GKE cluster on GCP [\[source\]](#). "During this time no other entity - no other engineer - can apply changes to the configuration." [\[source\]](#). This is an even bigger problem when you have a monolithic setup, with a lot of dependencies. So if one developer is updating the GKE cluster, then another developer may be blocked from updating a database or a networking rule.

Another challenge with Terraform state is that Terraforms state can easily go out of date with reality. This is called *configuration drift* [\[source\]](#) and [\[source\]](#). If the "terraform apply"-command is not run on a regular basis, the actual state can drift away from the declared/desired state. This means the state do no longer reflect the real world. This can create issues when later mutating the stored state, which can make the stored state unusable because it is so far from the actual state.

This can both be a gift and a curse. If it is an emergency, then it is possible to modify the terraform-created-resource manually through some other service (e.g., a person could change a network rule manually through the Google Cloud Platform) without it being reverted by some automated tool.

So the Terraform state can either be updated by an manual task (e.g. a developer manually creating a database), a triggered automated task (e.g. a deployment pipeline that applies the newly changed Terraform files - e.g [Atlantis](#) or Terraform Cloud), or some GitOps tool that continuously syncs the actual state with the declared state stored in a repo (or elsewhere).

### 5.2.1.3. State automation

You could install an automated tool or script that just does this "terraform apply" on a regular basis to ensure that there is no *configuration drift*. This is a reasonable approach, but then you are essentially creating a system that works just like a control plane. So instead of using a tool with all its issues and then patching some of the issues by wrapping it in some automation tool/script... why not just use a control plane that was built to solve exactly with that?

Kubernetes stores desired state, and the internal components try to keep the actual state as close as possible to the desired state. The state is stored as Kubernetes objects declared in YAML. Why not

store the same information usually stored in Terraform state inside Kubernetes instead?

An operator (control plane) running on Kubernetes could automatically sync (similar to continuously running `terraform apply`) the actual infrastructure with the declared state in YAML.

Automated controller logic that reconciles desired state with actual state [\[source\]](#)

This is where tools like *Crossplane*, Google's *Config Connector*, and AWS' *Controllers for Kubernetes* come into play. This paper will focus on Crossplane because it is built as a foundation for control planes in general and not only focuses on a single cloud provider.

Even though the paper highlights Crossplane the

#### **5.2.1.4. Crossplane as an alternative**

The most popular cloud-native control plane tool for handling external state is *Crossplane*.

Crossplane is a CNCF project that tries to streamline cloud providers APIs.

Crossplane tries to follow the success of Terraform and apply some of the same concepts to Kubernetes. Terraform has the concept of *providers*. A Terraform provider is a Terraform plugin that allows users to manage an external API. "Terraform uses providers to provision resources, which describe one or more infrastructure objects like virtual networks and compute instances. Each provider on the Terraform Registry has documentation detailing available resources and their configuration options." [\[source\]](#). Crossplane mimics this concept, so external organizations can create a plugin that integrates with crossplane providing the user the ability to provision external resources.

Crossplane can be used to provision resources for all cloud providers if the cloud provider has created a Crossplane provider for it.

As a company/organization it can be beneficial to have the option to be multi-cloud, because different cloud providers have different offerings.

Terraform uses HashiCorp configuration language (HCL), while crossplane use `YAML` and follows the same structure conventions as Kubernetes manifests.

It can be a big jump to go from Terraform to Control planes, which is why tools like *Kubeform* and *the Terraform provider for Crossplane* exists. Kubeform provides auto-generated Kubernetes CRDs for Terraform resources so that you can manage any cloud infrastructure in a Kubernetes native way. This requires you to rewrite your Terraform JSON to Kubernetes CRDs, so if that is too time consuming you can instead you can use Crossplane's Terraform provider. This provider lets you copy-paste your Terraform syntax directly into a CRD and Crossplane will in concept run `terraform apply` automaticity. This could be an intermediate step before doing a complete transition from Terraform to Crossplane.

Crossplane will be described in greater detail in the *Managing External State*-section.

## 6. Test Application

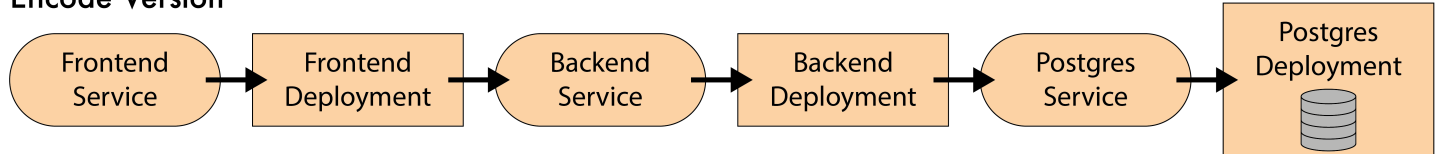
In order to test the implementation presented in the *Implementation*-section, I need a test application that run on the infrastructure and demonstrate its capabilities.

To do this i have used Eficode's, public `quotes-flask` application that they use for educational purposes. It is a simple application consists of a frontend, backend, and a database.

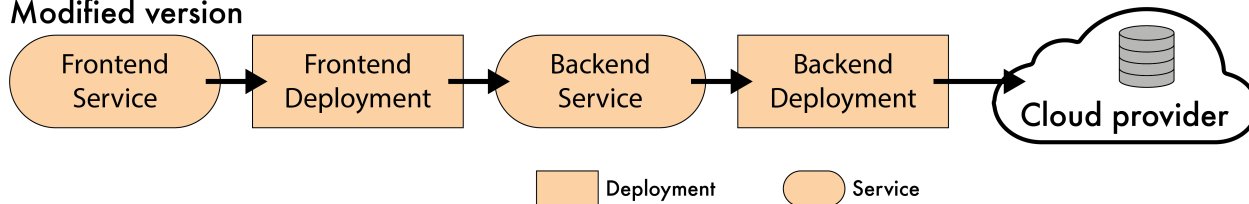
The frontend is a website where you can post and retrieve "quotes". The quotes are posted and sent to the backend-service which then stores the data in postgres database.

This system meant to be run in kubernetes and the repository already contains YAML-files. The system uses a postgres database running in a separate pod. To showcase the my implementations ability to provision database resources on cloud-providers i have replaced the postgres-database-pod, with an managed database running in a cloud provider, but besides that i have not changed overall architecture.

### Eficode Version



### Modified version



This setup is supposed to represent an actual production ready application a small business may want to run on a cloud provider. The evaluation of this project will partially be based on how well the implementation managed to host/deploy/run this test application and what implications/challenges it may bring.

The Quote demo services in this setup exists in both a AWS version and GCP version, where each of them connects to a different cloud provider's postgres database service. This will be covered in greater detail in section XXX below.

## 7. Implementation



This section will describe how I suggest building an universal control plane within Kubernetes for handling internal and external resources. The implementation strives to imitate a production ready system for a small company with website running in a production and staging environment in the cloud.

The main idea of this implementation is having a single cluster that works as an control plane. This cluster will provision other cluster and deploy software to them.

For the section I'll introduce two names: `core cluster` and `app cluster`. The `core cluster` is the control plane for managing your infrastructure and software environment. The `app clusters` is a shared term for all the clusters where business logic is supposed to run. For instance, a company may have two `app cluster`s in the form of a production cluster and a staging cluster. The `core cluster` that hosts all the shared services between different `app cluster` environments.

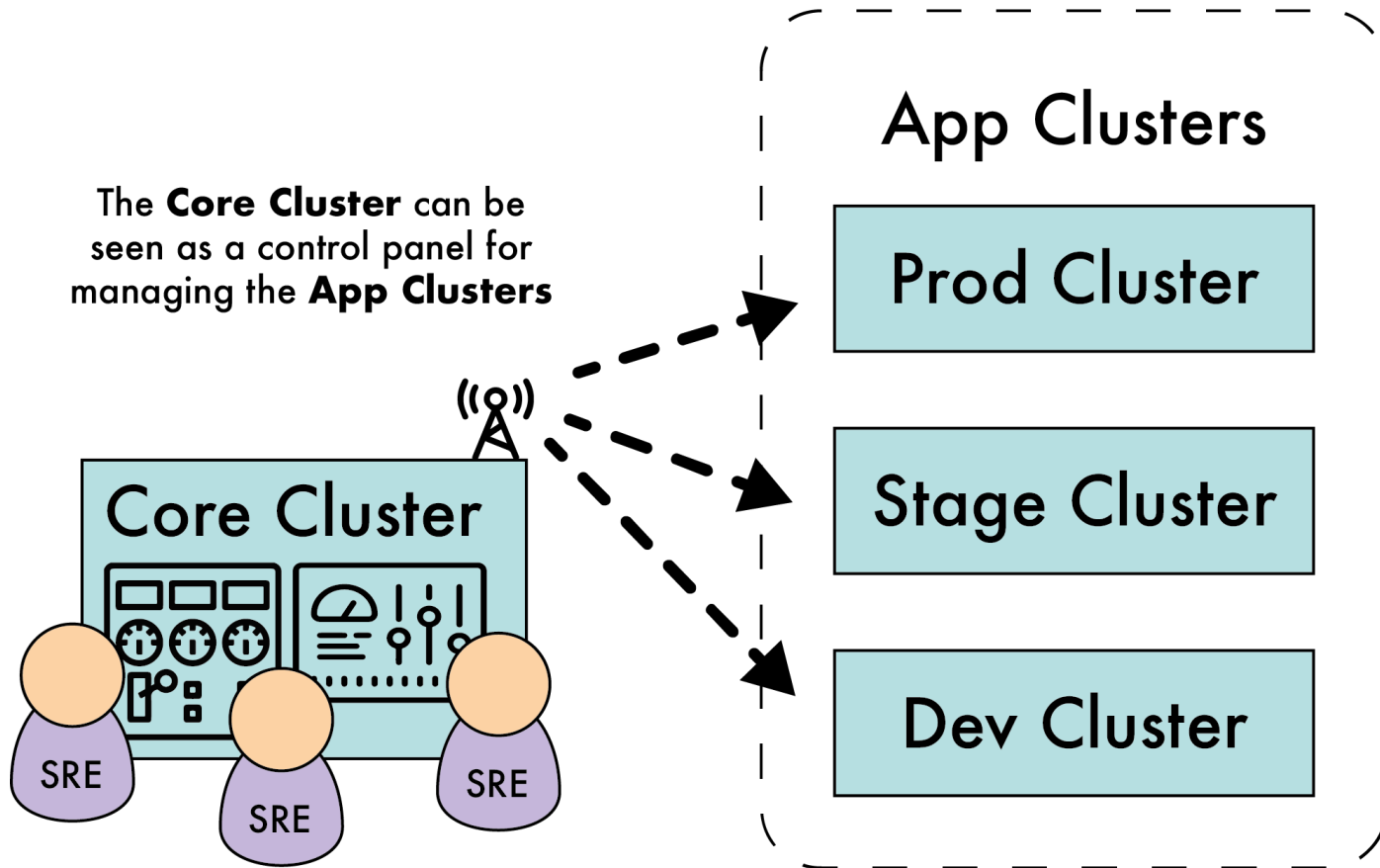


Figure X: An visualization/drawing of how SREs/The infrastructure team manage `app clusters` through the `core cluster`.

Only the infrastructure teams is supposed to interact with `core cluster` directly - while the application developers are suppose to only care about getting there workload running on the `app cluster`s.

The `core cluster` will use Crossplane for provisioning cloud resources and use ArgoCD to deploy and manage all services that running in the core cluster and the app clusters. Crossplane and ArgoCD are both open source tools funded by the CNCF. They are created as Control planes for Kubernetes and together they can be used to create a control for managing your whole multi-cloud multi-environment infrastructure.

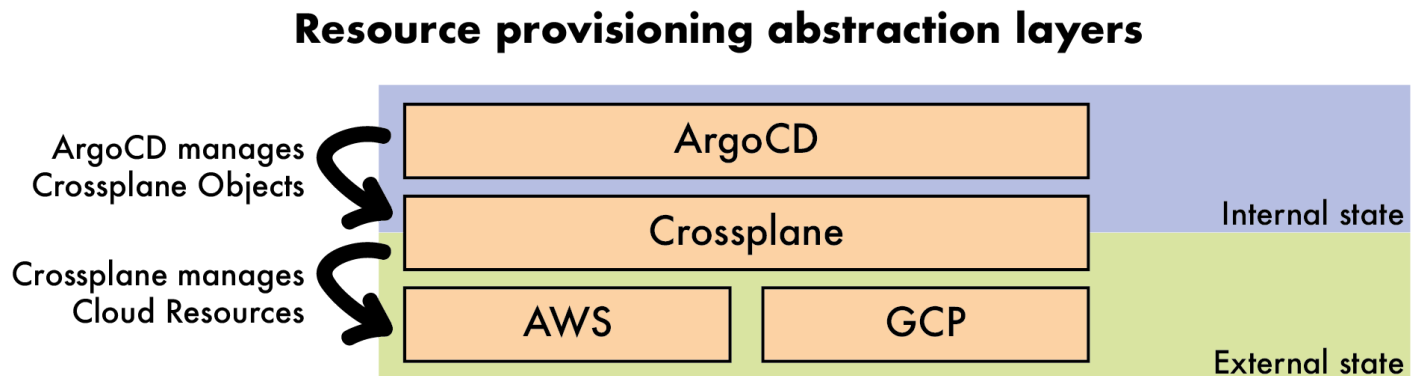


Figure X: An visualization of how ArgoCD and Crossplane works together to provision cloud resources.

ArgoCD handles all internal state, while Crossplane handles all external states - Combined can they be used as a universal control plane.

As mentioned previously the question is not so much if Crossplane or ArgoCD are great tools or not - but more about that if paradigm of control planes are good in general. As Eficode states: "If Crossplane does not strike the right balance and abstraction level, the next control plane will." [\[source\]](#)

This setup can easily be extended by another tools. Crossplane is currently focused on cloud-providers (but nothing prevents it from expanding to new topics in the future), so if you want to manage external resources that is not cloud-related you could just install a control plane for that as well. The point is that for the use-cases i have presented only using ArgoCD and Crossplane is sufficient, but other control planes could easily be added if more features were needed.

## 7.1. List of tools/technologies used in this implementation

### ArgoCD

ArgoCD is a GitOps tool using control planes and it runs inside Kubernetes. ArgoCD is used for this implementation, because it more advanced UI features compared to similar tools. The two biggest GitOps Tools are FluxCD and ArgoCD. This implementation could also be build using FluxCD. FluxCD

and ArgoCD cover most of the same features, but the way you structure code looks a bit different. Both tools would be good candidates for building a universal control plane for kubernetes.

ArgoCD was accepted to CNCF on April 7, 2020 and is at the Incubating project maturity level [\[source\]](#).

## Crossplane

Crossplane is used in this implementation, because it is the only option if you want a control plane that works with multiple cloud providers (and is not just a Terraform copy-pasted into a control plane setup). If a multi-cloud architecture is not needed one could instead opt for Google's *Config Connector*, or AWS' *Controllers for Kubernetes*.

Crossplane was accepted to CNCF on June 23, 2020 and is at the Incubating project maturity level. [\[source\]](#)

## Google Cloud Platform

GCP was chosen as the main provider for cloud hosted kubernetes clusters because it less complex to use than AWS, but advanced and mature enough to work well with crossplane. Another choice would be DigitalOcean, but I experienced some issues with using Crossplane with DigitalOcean (also described in the *limitation* section). I didn't experiment with Microsoft Azure, since I had no prior experience working with them as a cloud provider. Both AWS and Azure would be potential alternative to GCP in this implementation.

## Kind

kind is used for running Kubernetes cluster locally. When developing and experimenting with this setup it can be beneficial to run the setup locally, because it can take a long time to provision clusters on cloud providers (e.g it often takes 10 minutes on GCP). There is many different tools for running Kubernetes locally, and many of them would probably work for this implementing, but the choice ended with Kind, because it is easy to setup and simple to use. Other alternatives could be *MicroK8s* or *Docker Desktop*.

## Gum

Gum is a simple command line tool for making interactive scripts. When you want to start any type of custom made system from a terminal it usually involve creating multiple scripts for doing some of the initial bootstrapping. Gum was chosen as a simple tool for interactively picking a configuration on runtime instead of having to remember command parameters or creating static config-script.

## Helm and Kustomize

Helm and Kustomize is used to template and install kubernetes resources. Helm is a package manager for Kubernetes. ArgoCd installs external packages (like Crossplane) using Helm. Kustomize

is used for handling templating of my own kubernetes manifests. One could choose to not use kustomize and instead put everything into helm charts, as an alternative to this implementing.

## 7.2. Managing internal state

Everything deployed to the clusters are declared in yaml checked into git and read by ArgoCD.

ArgoCD can either be installed on each cluster individually only controlling the local state - or it can be installed on shared cluster which then handles the deployment to multiple clusters.

Installing ArgoCD on each cluster means there is no shared interface of all the infrastructure running across clusters. You would have to have multiple endpoints and multiple argo-profiles/-credentials for each argo instance running in each cluster, which may not be desirable if you run infrastructure on large scale. Furthermore it also consumes more resources to run all ArgoCDs components on each cluster (vs. only it on a single cluster), which may be a consideration if your company's budget is tight.

For this implementation a single instance of ArgoCD will run on the `core-cluster` and deploy and manage all the Kubernetes Object running in both the core cluster and the app clusters.

ArgoCD groups YAML-files/folders into an abstraction called *Applications*. Applications is just a normal kubernetes manifest, where you specify a path to a resource you want to deploy, a destination cluster, and some configuration parameters. You can structure (and nest) these groupings however you want, but you usually want smaller groupings, so you manage/sync them individually with more fine-grained control. e.g. Deploying Crossplane provisioned database separately from the Crossplane provisioned Kubernetes Cluster. This way you don't have to have use the same sync-policy for both groupings of resources. e.g. you may have pruning (auto-delete) disabled on the database, to ensure databases are not deleted by mistake.

Based on this philosophy of separation i have chosen to structure my applications like this:

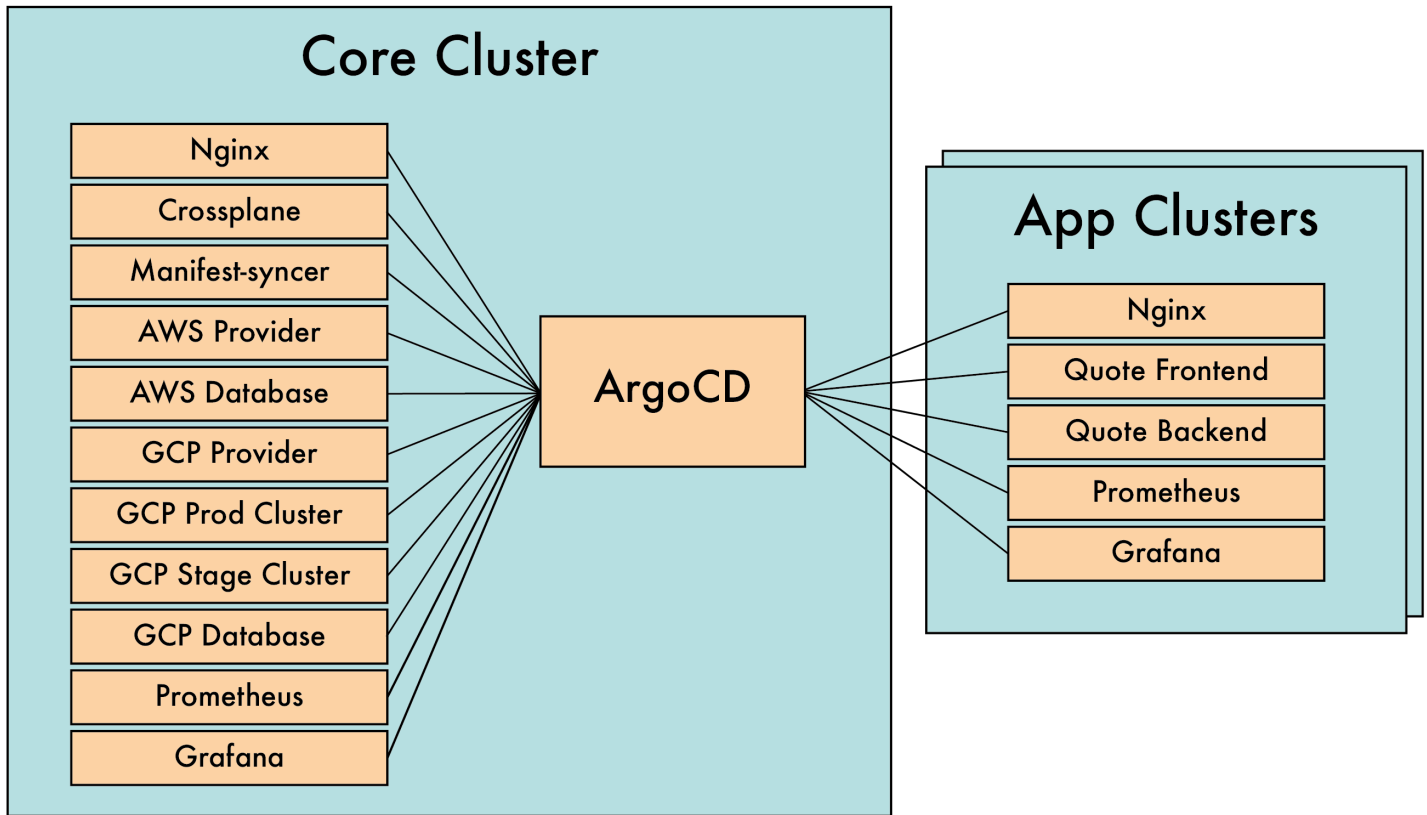


Figure X: An illustration of what packages/services ArgoCD installs and on which cluster.

## Other applications/packages

Besides Crossplane, ArgoCD also installed other packages/services:

### NGINX

In order to call the Quote Frontend from outside kubernetes we need to setup ingress. NGINX is an ingress controller that acts as a reverse proxy and load-balancer and handles all external traffic into the cluster. A cluster needs a ingress controller in order to call the endpoints inside kubernetes from outside kubernetes.

### Prometheus and Grafana

Prometheus and Grafana is a famous open source monitoring stack. This stack is not strictly needed to run the test applicaiton, but it is used to resemble a realistic setup you would see at a company. It is installed on both the core clusters and the app clusters, so it is possible to observe the resource usage.

## 7.2.2. Eventual consistency

At its core all ArgoCD is reads from a given branch on a given repository and applies all the resources that it finds to Kubernetes. By default there is no order to this process, but ArgoCD will just apply all

the manifests and then Kubernetes will handle the rest.

In any modern software environment there exist dependencies. The amount of dependencies depends on how well your system is decoupled.

If a typical company would have to spin up their entire infrastructure from scratch, it would probably include a lot of sequential steps in a specific order, because some of their services need other service to run.

Doing sequential deployments through a script often takes a long time, because it runs sequentially and not in parallel. With Eventual consistency, you can much easier run multiple steps at the same time. Kubernetes is full of eventual consistency. There is no order of when which resources/events are created/handled - instead everything will just eventually be setup/running. Applying Kubernetes resources with ArgoCD works the same way. If ArgoCD fails to deploy one of these Applications (because some dependency may be missing) it will just automatically try again in a minute. This means I can apply our entire infrastructure at once with ArgoCD, and ArgoCD will make sure everything will be deployed with eventual consistency even though there are broken dependencies temporarily in the process. This also applies every time you update something in the infrastructure. Configuration and workload will be applied and scheduled whenever ArgoCD eventually syncs its state with whatever is stored in the chosen git repository.

### 7.2.3. Repository structure

The structure for this implementation is split up in 3 repositories. One ArgoCD Synced repository for the `core-cluster`. A second ArgoCD synced repository for syncing with `app-cluster` and a general repository with code and scripts for bootstrapping the system.

```
root
├── scripts-repo           # Bootstrapping scripts
├── app-cluster-gitops-repo # Only containing resources synced with Argo
└── core-cluster-gitops-repo # Only containing resources synced with Argo
```

The GitOps synced repositories do not contain anything else than resources synced with ArgoCD. Only automated tools and scripts commit changes to the repositories.

You could choose to store the `core-cluster` and `app-cluster` in the same repository and store every argo-application for the whole organization in single repository. From a technical standpoint there is no problem in this solution and it may even be preferred because it will be easier to update the structure for a system that requires changes in multiple-clusters, at the same time.

```

root
├── scripts-repo          # Bootstrapping scripts
└── infrastructure-gitops-repo
    ├── app-cluster      # Only containing resources synced with Argo
    └── core-cluster      # Only containing resources synced with Argo

```

On the other hand you may not want everyone in organization have read-access to all infrastructure. The write-access would not be a problem since you can e.g. use `CODEOWNERS` [on github](#).

The main point here is that there are many ways to structure your GitOps synced repositories, and it all depends on what kind of needs you have in your organization.

Below we can see the folder structure of the `Core Cluster` and `App Cluster`. Most resource that is applied by ArgoCD is structured/built with Kustomize using the [base-overlay-pattern](#), thus why we have all the `base` and `overlays` folders.

### App Cluster Git Repo:

```

app-cluster-gitops-repo
├── argo-bootstrap
│   ├── prod
│   └── stage
├── example-database-eficode-aws
│   ├── base
│   │   ├── backend
│   │   └── frontend
│   └── overlays
│       ├── prod
│       └── stage
├── example-database-eficode-gcp
│   ├── base
│   │   ├── backend
│   │   └── frontend
│   └── overlays
│       ├── prod
│       └── stage
└── kube-applications
    ├── base
    └── overlays
        ├── prod
        └── stage

```

### Core Cluster Git Repo:

```

Core-Cluster
├── projects                # Declaration of how Argo Applications are grouped
├── argo-bootstrap
│   ├── gcp
│   └── kind
├── argo-config            # Ingress configuration for accessing the argo server on GCP or kind.
│   ├── base
│   └── overlays
│       ├── gcp
│       └── kind
├── aws-provider
├── aws-database
├── gcp-provider
├── gcp-database
├── gcp-clusters
│   ├── base
│   └── overlays
│       ├── prod
│       ├── prod-pre
│       ├── stage
│       └── stage-pre
├── manifest-syncer
└── kube-applications
    ├── base
    ├── envs
    │   ├── core
    │   └── experimental
    └── host
        ├── gcp
        └── kind

```

## 7.3. Managing External State

In this implementation I use crossplane for managing the external resources. Crossplane is a control plane that runs inside kubernetes that makes sure that the external resourced described in yaml is in sync with the state declared in kubernetes.

Here you can think about Terraform and the provider-integrations that exists. The developer creates a provider-configuration and is then able to create resources on that provider's infrastructure. It is now up to the provider to manage and ensure that the state running on their infrastructure matches the desired state declared in your kubernetes cluster.

Currently Crossplane supports AWS, GCP and Azure as cloud providers. A DigitalOcean provider is also in active development [[source](#)].



As an example, in order to provision a resource on AWS you need to create a `Provider` , `ProviderConfig` and *the resource you want*. So if we want to provision a postgres database on AWS we apply the following configuration to kubernetes (with Crossplane installed):

```
apiVersion: pkg.crossplane.io/v1
kind: Provider
metadata:
  name: aws-provider
spec:
  package: crossplane/provider-aws:v0.30.1
```

```
apiVersion: aws.crossplane.io/v1beta1
kind: ProviderConfig
metadata:
  name: aws-provider-config
spec:
  credentials:
    source: Secret
    secretRef:
      namespace: crossplane-system
      name: aws-creds
      key: creds
```

```
apiVersion: database.aws.crossplane.io/v1beta1
kind: RDSInstance
metadata:
  name: postgres-instance
spec:
  forProvider:
    region: eu-central-1
    dbInstanceClass: db.t2.small
    masterUsername: masteruser
    engine: postgres
    engineVersion: '12.10'
    skipFinalSnapshotBeforeDeletion: true
    publiclyAccessible: true
    allocatedStorage: 20
  providerConfigRef:
    name: aws-provider-config
  writeConnectionSecretToRef:
    namespace: crossplane-system
    name: aws-database-conn
```

These yaml files are read by a *controller* (which is provided by the provider as a *helm-chart*). As a developer you do not care how it is implemented behind the scene, you just know that the controller continuously tries to make sure they desired state is upheld.

The controller will read the above `RDSInstance` and check that such an instance exist on the AWS account referenced in the `ProviderConfig`'s `credentials` -section. This is how crossplane is able to create DNS Records, VPC's, Subnets, Node Pools, K8s Clusters and databases in this setup. All this can be found in the `/gcp-clusters` in `core-cluster-argo-repo`.

Depending on which cloud-provider you are able to create most cloud resources offered by that cloud provider.

### **Could be any other tool as well.**

We have used crossplane because it demonstrates how it can transform kubernetes into a control plane managing external resources, but there could easily be created other tool in the future.

This paper is not trying to argue that Crossplane is a perfect tool but rather that crossplane is just an example of tool that can be used to manage external resources from kubernetes.

Crossplane is built to be highly extendable (just like Terraform), making it easy to create new providers. Currently not a lot of providers exist, but I could imagine Datadog could create a crossplane-provider (equal to their Terraform provider integration), where the user could specify their dashboard declared in `yaml` and applied to the cluster. With Terraform the user usually have to create the dashboard in Terraform and store it on bucket. This works fine in practice, but one could argue that we don't need to store that state in a bucket, but instead we could just store the declared state directly in kubernetes together with the services you are monitoring.

### **One instance or multiple instances of crossplane?**

Just like ArgoCD, you can either install crossplane on each cluster or install it in a shared cluster. Just like with ArgoCD it provides much better visibility to only have a single instance running, making it easier to see which external resources are running outside kubernetes.

Running crossplane on a shared/core cluster also decouples the external resources from the actual clusters. This means that you don't lose the connection with the staging-database, just because you close down staging-cluster temporary. You rather want to your external infrastructure to be managed from a cluster that you know will remain up and running.

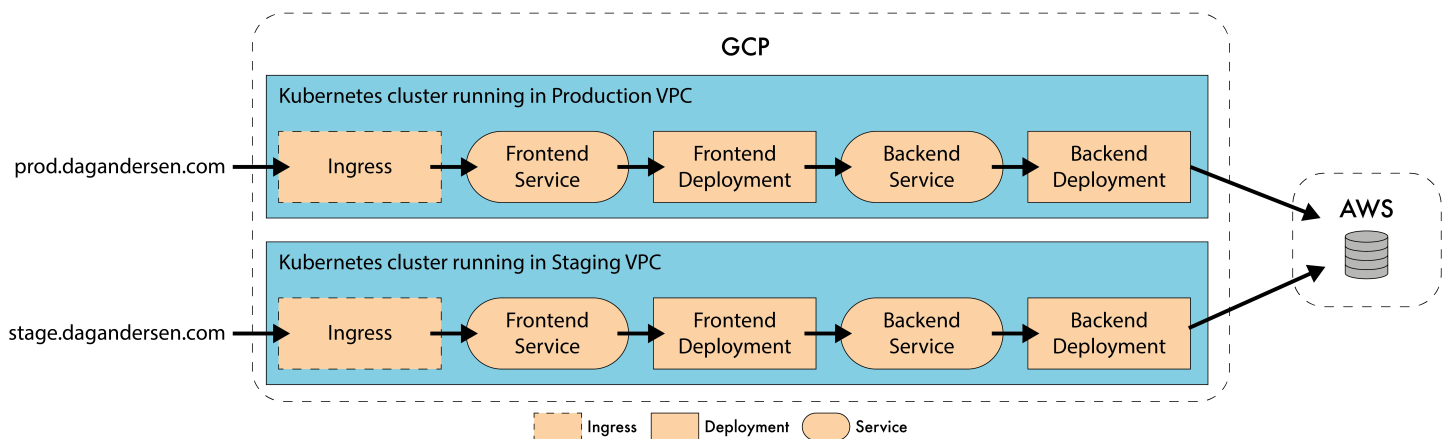
An important detail is that when crossplane creates a resource (e.g. database instance) it stores the connection details in the cluster which crossplane is running on. The problem here is that you often need the credentials in app clusters (e.g. you want your services running in the production environment to connect to the production database). There are many ways to handle secrets/credentials, but more on this in section *Distributing secrets*.

## 7.4. Demonstration Application

In order to demonstrate that all the components actually work i have build this setup to show how both internal and external state management plays together to have a fully declarative infrastructure setup managed from inside kubernetes.

In this setup I have two environments running: production and staging. Each environment runs in its own VPN (and subnetwork) and subdomain on GCP. Both environments can connect to a shared database either running on AWS or GCP. The demonstrations uses AWS to show that this kind of setup works across different cloud providers. As described in the XXXX section, each environment runs a simple frontend service, which calls a backend service, which then stores its data on the database. In practice this results in an `ingress` object , two `service` object, and two `deployment` object per environment.

This is proof of concept. This is paper is not arguing that this is good software architecture.



The production and staging environment runs completely separate on GCP. This project makes it possible to (in theoretically at least) scale the number of workload-environments to infinity through the `core-cluster` and `laC` based *GitOps*.

Crossplane does not have a UI, but you can interact with it with `kubectl` like any other kubernetes resource. Running `kubectl get managed` will print a list of all the resources managed by crossplane. The external resources used in this demo is showed blow.

subnetwork.compute.gcp.crossplane.io/crossplane-subnetwork-prod	True	True						
subnetwork.compute.gcp.crossplane.io/crossplane-subnetwork-stage	True	True						

NAME	READY	SYNCED						
network.compute.gcp.crossplane.io/crossplane-network-prod	True	True						
network.compute.gcp.crossplane.io/crossplane-network-stage	True	True						

NAME	READY	SYNCED	DNS NAME					
resourcerecordset.dns.gcp.crossplane.io/aws.db.prod.dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/aws.db.stage.dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/gcp.db.prod.dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/gcp.db.stage.dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/prod.dagandersen.com	True	True						
resourcerecordset.dns.gcp.crossplane.io/stage.dagandersen.com	True	True						

NAME	READY	SYNCED	STATE	ENDPOINT	LOCATION	AGE		
cluster.container.gcp.crossplane.io/gcp-k8s-prod	True	True	RUNNING	34.163.165.111	europa-west9-a	13m		
cluster.container.gcp.crossplane.io/gcp-k8s-stage	True	True	RUNNING	34.163.29.144	europa-west9-a	13m		

NAME	READY	SYNCED	STATE	CLUSTER-REF	AGE			
nodepool.container.gcp.crossplane.io/gcp-k8s-np-prod	True	True	RUNNING	gcp-k8s-prod	13m			
nodepool.container.gcp.crossplane.io/gcp-k8s-np-stage	True	True	RUNNING	gcp-k8s-stage	13m			

NAME	READY	SYNCED	STATE	ENGINE	VERSION	AGE		
rdsinstance.database.aws.crossplane.io/aws-database-postgres-instance	True	True	available	postgres	12.10	13m		

Here we can see that two VPCs ( `network.compute.gcp` ), two subnets ( `subnetwork.compute.gcp` ), six DNS records ( `resourcerecordset.dns.gcp` ), two k8s clusters ( `cluster.container.gcp` ), and two node pools ( `nodepool.container.gcp` ) are running on GCP and a single database instance ( `rdsinstance.database.aws` ) is running on AWS.

## 7.5. Distributing secrets

When crossplane creates a resource (e.g. kubernetes cluster or database) on a cloud provider it stores the connection details (e.g access credentials) in the cluster where crossplane is installed - but in a setup with a `core-cluster` , that doesn't have any business logic running it is not very useful. The connection details to a database is needed in the production or staging environment.

This show how popular tools like ArgoCD and Crossplane does not necessary go well together by default. These small gaps can easily occur when we are using many different tools from the kubernetes ecosystem, that was not necessarily meant to be used in conjunction with each other and does not have a native integration between the tools. As an infrastructure team you may have to close these cap yourself, if you can't find an off-the-shelf component from GitHub that solves your problem.

Many of these small gaps can be solved with a few scripts, a cronjob running a script, or a small standalone service.

I am filling this hole: <https://github.com/crossplane-contrib/provider-argocd/issues/13>

There is a few ways of overcoming this secret-distribution challenge. The most naive one would be to create a manual step where the developer needs to some home copy the credentials to the production cluster, whenever he/she decides to create a cluster.

Another way of doing this is using a some kind of secret-vault where the credentials are stored during the creation of the database and each cloud environment can read the credentials directly from the vault when needed.

This may be considered considered best practice currently and it comes with some nice benefits (which is beyond the scope of this paper) - but it none the less introduces even more tools/concepts to our infrastructure, which may put even more workload on a small infrastructure team.

This is why i have created a much simpler solution.

As usual there is many ways of closing a gap, but we need to keep in mind we want a declarative approach, so we want the distribution to happen eventually and not a specific point in the rollout of a new cluster or new secret.

Therefore i have implemented a service named, `manifest-syncer`. The `manifest-syncer` purpose is to mirror secrets from its host cluster to target.

The service makes use of `CustomResourceDefinitions`, so the user of the service does not need to configure the service. They just deploy the container and create `yaml` files describing what they want copied.

The developer can then declare what he wants copied and to where.

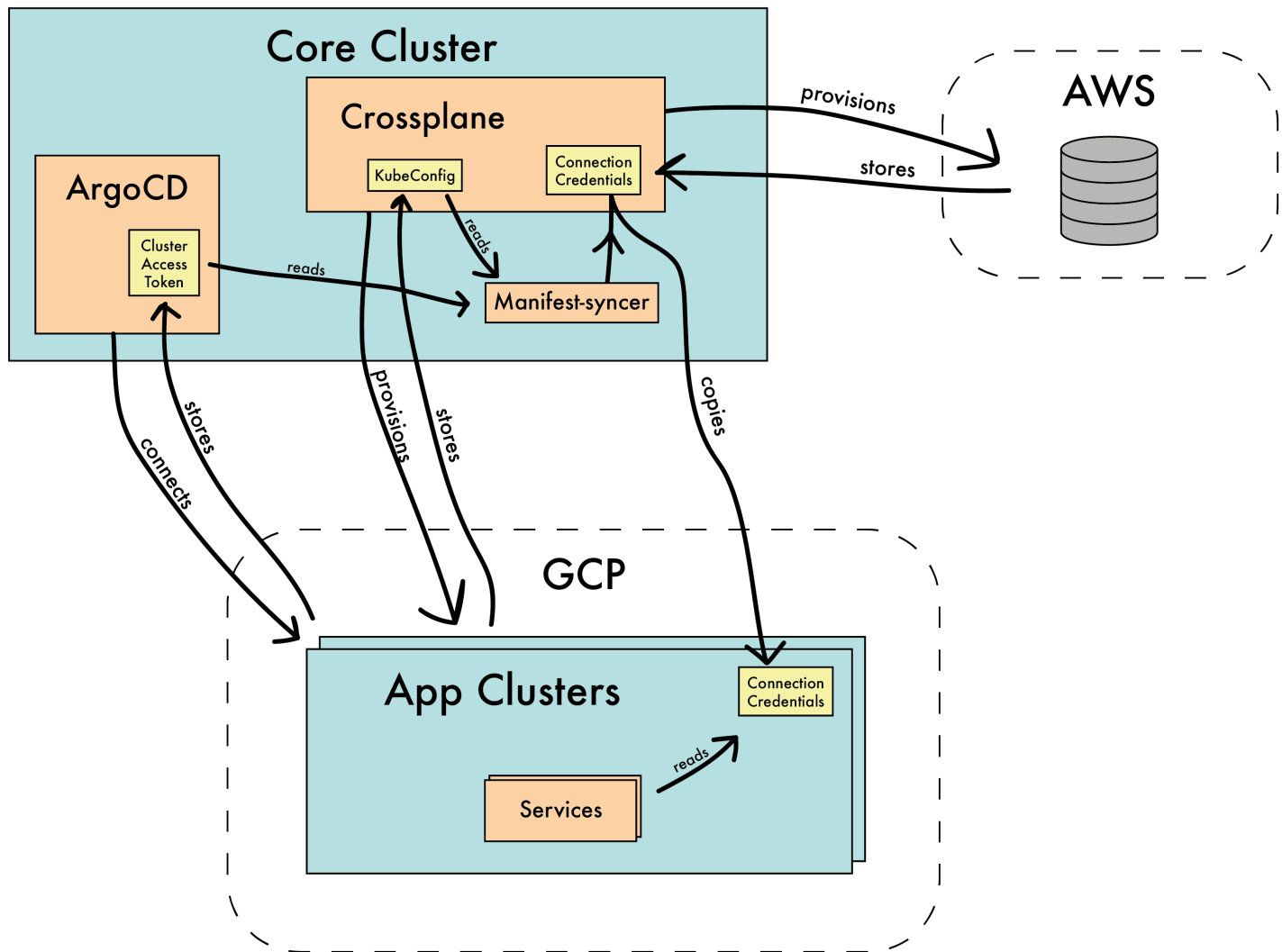
```
apiVersion: dagandersen.com/v1
kind: Syncer
metadata:
  name: secret-syncer
  annotations:
    argocd.argoproj.io/sync-options: SkipDryRunOnMissingResource=true
spec:
  data:
    - sourceName: gcp-database-conn
      sourceNamespace: crossplane-system
      kinds: secret
      targetCluster: gcp-cluster-prod
      targetNamespace: default
```

On this example we can se how we specify the secret named, `gcp-database-conn`, in namespace, `crossplane-system`, should be copied to namespace, `default`, on the cluster named, `gcp-cluster-prod`.

Note: `argocd.argoproj.io/sync-options: SkipDryRunOnMissingResource=true` is added to ensure that ArgoCD does not fail the deployment on purpose, because `Syncer` does not exist as custom resource at deployment time. This can happen when `Syncer` -manifest is *applied*

before the `manifest-syncer` is deployed.

This annotations is needed, because we do not know when each service will be deployed to kubernetes, but we just know it will be at some point because of eventual consistency.



This `manifest-syncer` is needed in order for the business workload to access the credentials for the database.

## 8. Use in practice

So far this paper has explained what control planes are and how one can build an entire infrastructure setup only using kubernetes.

The *implementation*-section described how one instance of a system using kubernetes and control planes could look, but we not yet covered how we use the setup after creation. As we know, systems

are not built once and never touched again. The setup/system needs to be maintainable and modifiable over time.

If we want to convince ourself that this is actually a elegant setup, we first need to envision how it would be used in practice in a company.

It is important to say there is many philosophies and strategies when it comes to deployment of software. This paper gives an example of how to use ArgoCD together with Crossplane, but others may choose to structure their code differently. E.g if a user choose to use FluxCD (instead of ArgoCD) and Google's Config Connector, the optimal structure may look very different.

In this section we will go through some examples of how such a system would work in practice if implemented in a company.

*The use-cases are:*

- Developer creating a new service with an associated database
- Deploying a new service version to the multiple cloud environments
- Spinning up the cluster from scratch

So now the question is... how is actually used in practice?

Keep in mind that many of the tools used in this setup is under active development, so the feature set of these tools may change in future and change the workflows.

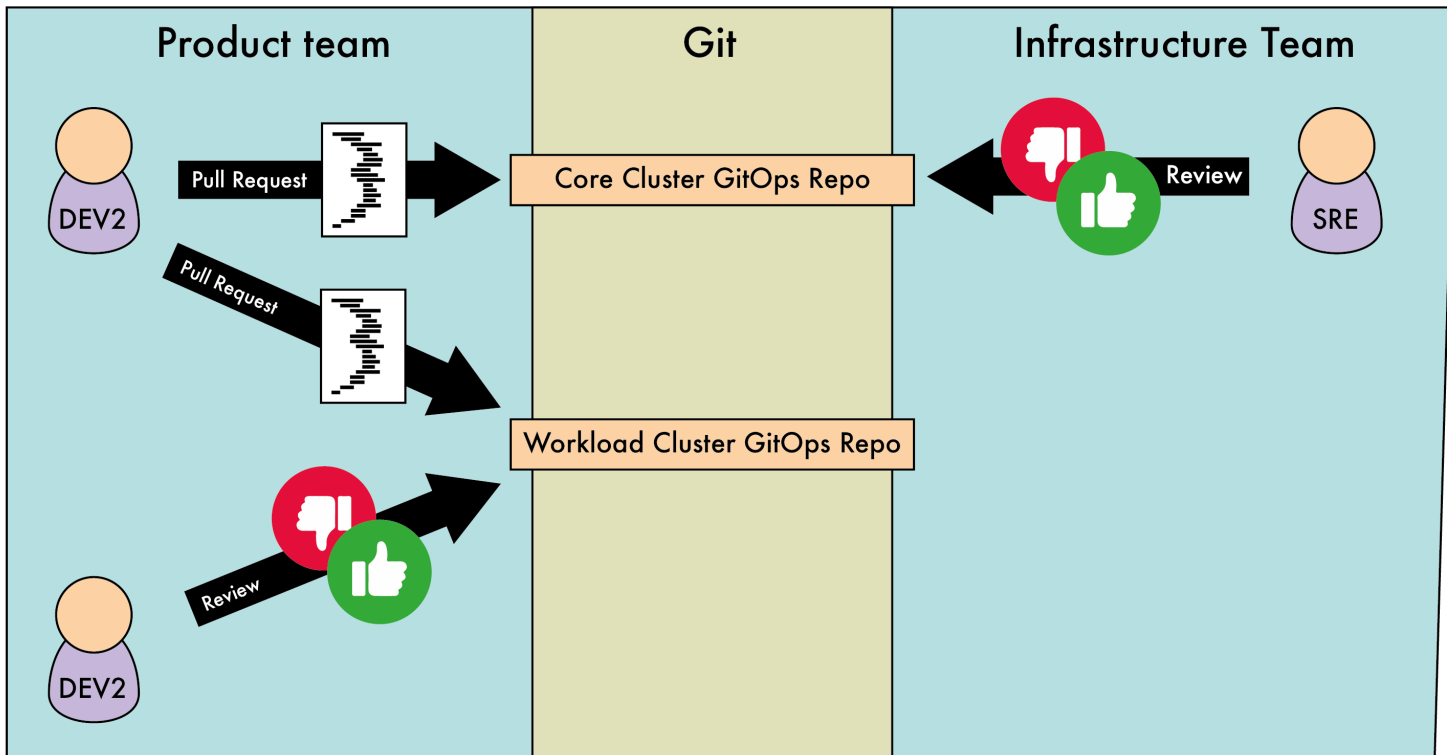
These use-case examples assumes that the folder-structure is the same as described in the *Repository Structure*-section.

## 8.0.1. Developer creating a new service with an associated database

*So how would the workflow be if a developer wants to create a new service with a new database instance?*

1. The developer creates a *pull request* to the `core-cluster-gitops-repo` with manifests describing the database instance and a `syncer` object for distributing the connection details to the database (as explained in *Distributing secrets*-section )
2. The developer creates a *pull request* to the `app-cluster-gitops-repo` with the `yaml` describing all kubernetes objects required. This could for instance be `yaml` describing `ingress` , `service` , and `deployment` .

Depending on the policy for this imaginary company it may be a person from the infrastructure team approving the provisioning of this new database, while it may be a person from the development team approving the normal app related kubernetes resources.



## 8.0.2. Deploying a new service version to the multiple cloud environments

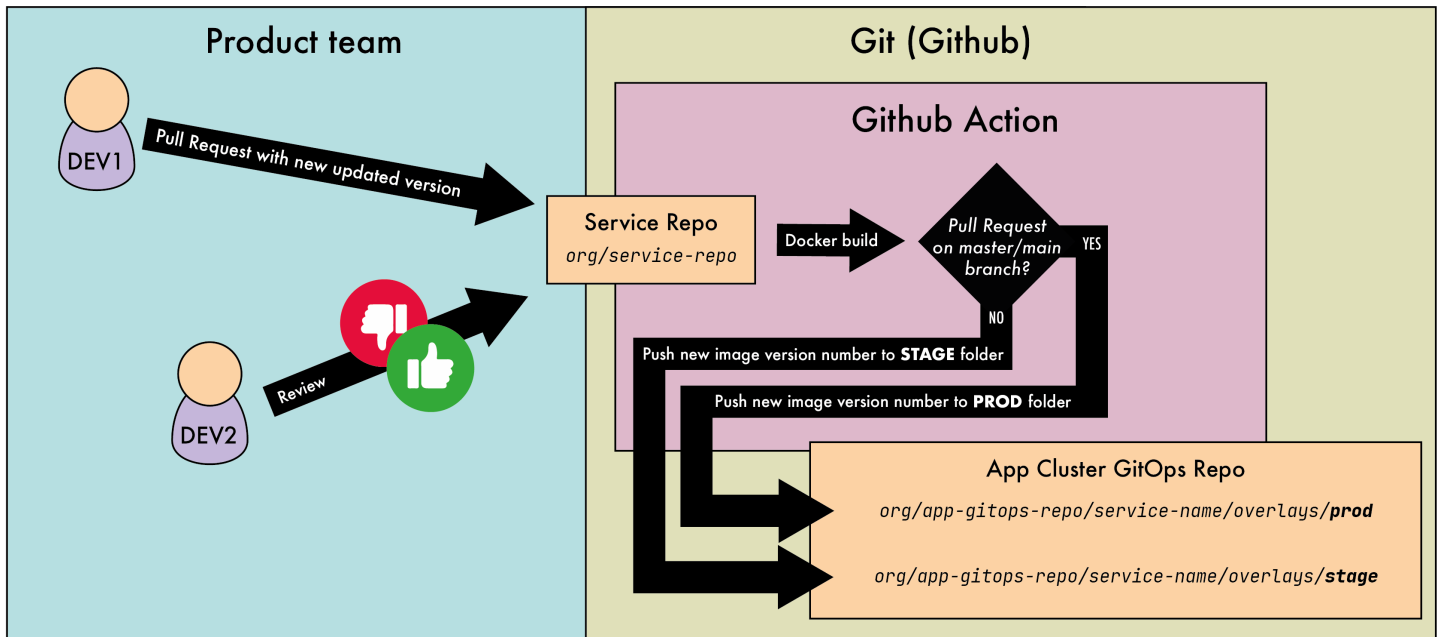
*So how would the workflow be if a developer wants to update their service on e.g. the staging cluster?*

Most Argo Resources in this setup is generated using Kustomize. Kustomize use a folder pattern, where each configuration for a service is stored in the `overlay` folder. In this case the configuration *service A* for the production environment would be stored in `service-a/overlays/prod/`.

Lets assume a developer team has a containerized service named: `service-a`. When a new version of `service-a` needs to be deployed, the developer creates a new *pull request* with the committed changes. If commits are not on the main/master branch then the build pipeline builds the image and pushes it to e.g. dockerhub with a unique tag. In addition to that the pipeline also updates the service version in git-ops controlled repository with all the new tag. In this case the build system updates the `kustomization` -file in `/service-a/overlays/stage/` with the newest version that should be deployed to the staging cluster.



When the changes has been tested on the staging cluster and the PR has been merged into master/main, then the same process begins. The only difference is that the build-pipeline this time updates the `/service-a/overlays/prod/` instead.



The *Argo Project* (the organization behind all Argo tools) does not provide any opinionated standardized way of pushing a new commit with the new image tag/version. This usually ends up with each organization/team makes their own custom code for doing commit push to the GitOps-synced repo.

### 8.0.3. Spinning up the cluster form scratch

So how would the workflow be if an infrastructure engineer wants to spin up the entire setup from scratch? Essentially spinning up a core cluster, multiple app clusters and deploying every service/system described in the *managing internal state*-section.

1. Git pull the `scripts-repo / bootstrap repo` .
2. Run `make install-tools` in the root to pull down the dependencies.
3. Add your Cloud Provider and Git-repo credentials to the `./creds/` -folder.
4. Run `make start` in the root to start the interactive cli for choosing what resources to create.

```
> make start
```

```
Utilizing Kubernetes as an universal control plane!
```

```
Which core cluster should we create for you?
```

```
> local  
gcp
```

This interactive-cli experience can be replaced with something else. e.g. it would be possible to replace the CLI with a simple UI if that is preferred.

First you specify if you want the `core-cluster` to be running locally with `kind` or you want it to be run on *Google Cloud Platform*.

Other options can added relatively easily by adding scripts to the bootstrap-repo.

choosing `local` is preferred when developing, since it takes around 10 minutes to spin up a GCP cluster and it only takes 20 sec to spin-up a local kind cluster.

```
> make start
```

Utilizing Kubernetes as an universal control plane!

Which core cluster should we create for you?

Answer:  
local

What should be installed?

```
[ ] skip  
[ ] prod-cluster  
[x] stage-cluster  
[ ] gcp-database-example  
> [•] aws-database-example
```

You can either start everything up at once or start with `skip` and spin up whatever you need later.

You can run the `make start` command as many times as you want. It will detect that you already have a cluster running and ask if you want to delete the currently running version.

By default (by choosing `skip`) the script will spin up a local containerized kubernetes cluster using *kind* and install ArgoCD and deploy nginx (so you can connect to the cluster). ArgoCD will then apply all the crossplane related setup and apply the `manifest-syncer`. Now the baseline is set the `core cluster` can now be used as a control plane for spinning up external cloud resources, and deploy apps to external kubernetes clusters.

Spinning up everything depends if you run the core cluster locally or on GCP. Spinning up a GKE cluster on GCP takes around 10 minutes [\[source\]](#). So if you run your `core cluster` locally it results in ~15 minutes process to spin up the entire system, of which 10 of them is only waiting for GCP creating the `app clusters`. If you run your `core cluster` on GCP you have to wait an initial 10 minutes before the core clusters is created resulting in a combined wait time of ~25 minutes to spin up the entire system.

# 9. Discussion and evaluation of implementation

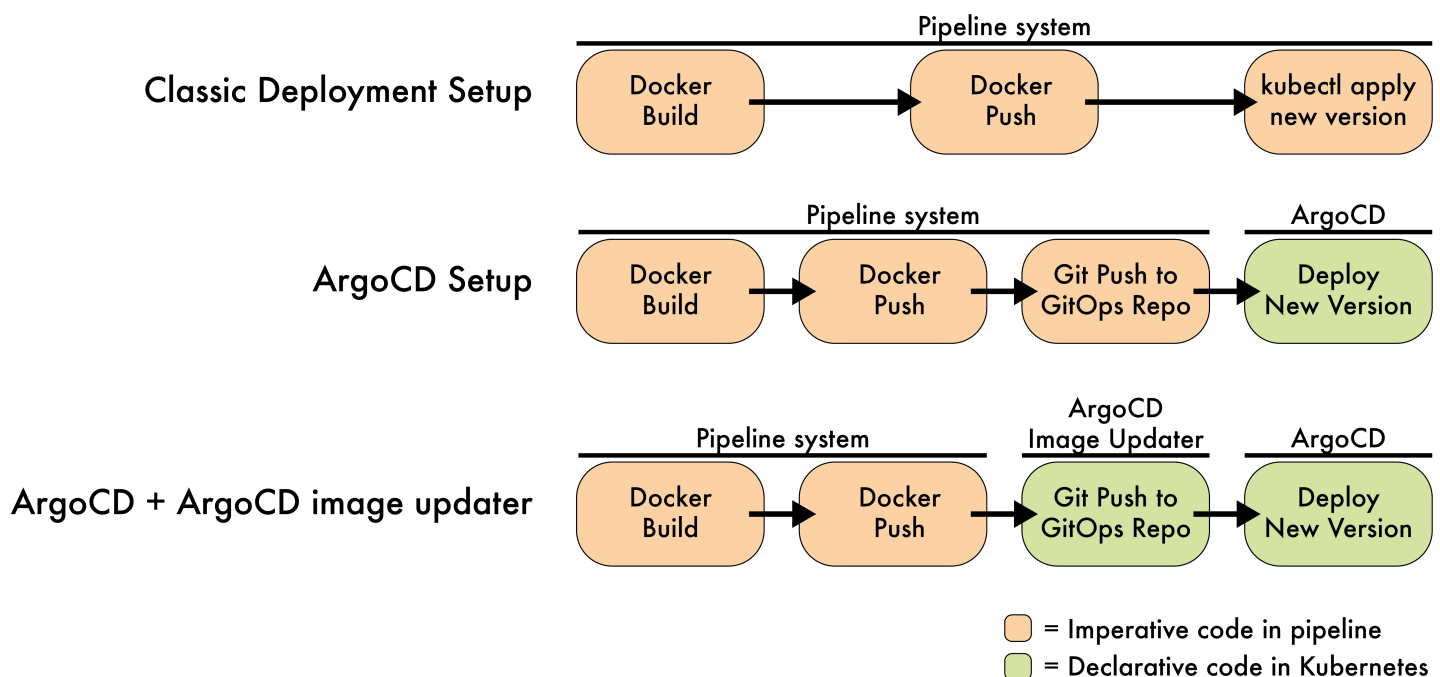
We have now explained how control planes work, how to build an entire system based on control planes, and showed how such a system could be used in practice.

Changing your infrastructure management to a paradigm of control planes will make you re-evaluate bla bla bla

This section will discuss some of the challenges and limitations of this setup. These topics will give Eficode a better baseline for discussion pros and cons with their client when discussing if they should move infrastructure built on control planes.

## 9.1. Build pipelines are still required

Switching to a GitOps workflow will not eliminate the need of pipelines. With the demonstrated setup you still need some kind of build-pipeline that runs whenever you have a new version of your app.



Classic build/deploy pipelines with Kubernetes consist of 3 steps: *build image*, *push image*, and *apply yaml changes* to Kubernetes. ArgoCD introduces a new step where the gitops-synced-repo is updated ( - there is no standardized way of updating this gitops-synced-repo, so it usually ends with custom script that pushes a new version to the repo). So with ArgoCD there is still 3 steps included in

the pipeline: The last step is just replaced with updating a repo instead of apply yaml changes to the cluster directly.

So in that sense we have not optimized much, we still have 3 steps in the deployment pipeline if we use GitOps/ArgoCD, but have now removed the need for direct access to the cluster from the pipelines. The pipeline instead needs access to the repo, where it suppose the push the changes.

As described in the *Declarative vs Imperative*-section we prefer declarative configuration when we have the option. All the steps in the pipelines are so far imperative. In order to avoid the need to create this custom imperative code that pushes the new configuration to the gitops-synced-repo, `argocd-image-updater` -project, was created. `argocd-image-updater` is part of the *Argo Project* and tries to tackle this challenge by moving the image-version-update-logic into a kubernetes operator. Now the pipeline system should only worry about building and pushing images. We tried the `argocd-image-updater` , but experience issues connecting to *Docker Hub* (as explained here: ). The `argo-image-updater` -project has been going on for at least 2 years, without reaching a stable state. So i will not consider this reliable option at the moment. The same tool exists in the FluxCD ecosystem [\[source\]](#). The Flux automated image updater may function as intended, but since we went with the ArgoCD ecosystem it was not reasonable to try out the flux version in this limited time frame.

Overall we have only managed to make the deployment process more complex by switching to GitOps/ArgoCD, but at the same time we have gained the well known benefints of GitOps [\[source\]](#) and more?]

## 9.2. Cost

When using kubernetes as a control plane we are running an extra kubernetes cluster, which is not free. Since this setup entails that we run a `core-cluster` (which doesn't provide any customer direct value) it will naturally mean that we spend more money on cloud resources than if we didn't run a `core-cluster` .

When running this implementation, more resources were required to run the `core-cluster` than the stage and production cluster examples combined. The ratio between the resources required by `core-cluster` and `workload-cluster` s, will depend on how much workload you run in production. But for my small examples the resources required by the `core-cluster` surpassed the other clusters combined, so if this setup would be adapted by a smaller company/team the economical aspect may be relevant.

For this setup to be running properly without issues 3 nodes of type "e2-medium" were needed. On monthly basis this is XX\$ just for running the `core-cluster` .

# Not everything can be in code.

Ip addresses needs to be reserved beforehand.

## 9.3. Security

Security is naturally aspect managing a software infrastructure. Terraform on its own does not have has no concept of access control[[source](#)] - You have to manage your access through credentials through the cloud provider. This works fine, but it is an extra set of credentials your organization has to manage.

With tools like Crossplane the development teams does not even need to have (write) access to the cloud provider. All external resources could be managed through tools like crossplane. Crossplane would be the only entity with (write) access to the cloud providers.

"The (cluster) administrator then uses the integrated Role Based Access Control (RBAC) to restrict what people can ask Crossplane to do on their behalf."[[source](#)]. All your access control can be moved to ArgoCD/kubectl - making kubernetes the only surface requiring access control.

This is also covered in Eficode's own article: "[Outgrowing Terraform and adopting control plane](#)".

If you want to take it one step further, ArgoCD could be the only entity with write-access to clusters - Enforcing that everything is version controlled (checked into git) and reviewed my multiple parties, before any change goes into production.

With tools like ArgoCD the development teams or automated pipelines does not need to have (write) access to the production cluster. All kubernetes objects could be managed through tools like ArgoCD.

The only problem here is that ArgoCD does not delete resources when deleted from git. ArgoCD simple does not track what changed between each commit, meaning that it does know what has been created or deleted - ArgoCD only know what the current state should be and nothing else. FluxCD is needed to solve this. FluxCD has the feature of *Garbage collection* that detects when resources are removed from git and deletes them in the cluster [[source](#)]. So with ArgoCD this results in a manual task of deleting resources which the developer may not have access too.

Combining ArgoCD and Crossplane you can create a workflow where external resources and business logic is checked into git and only goes into production through PRs with multiple reviewers.

How strict you want you permissions all depends on the policies and amount of trust in organization. This setup with Crossplane and ArgoCD makes it possible to create a system that is fairly restrictive.

## 9.4. Platform Engineering

Platform engineering is gaining popularity the last two years [\[source\]](#). This topic is a standalone topic and is not the main focus of this paper, but we just quickly want to highlight how control planes like *crossplane* can modernize your infrastructure, by embracing Platform Engineering and self-service. Crossplane has the concept of [Composite Resources](#), that works as an abstraction layer between the actual managed resource running on the cloud provider and the resource offered by the infrastructure team to the development teams. The developer then does not have to worry about where the database runs. The developer just requests a database in yaml, and the rest is handled by the abstraction created by the infrastructure/platform team. The abstraction becomes a platform for the developer to use - and they can self-service/provision infrastructure by using the provided abstraction. Developers will only interact directly with kubernetes and not any other cloud platform/portal.

*"This conversation is less about crossplane vs terraform. This is more about using crossplane to build your own kind of api server, your own control plane that highlights and exposes the resources and the properties that you want your people in your organization. This is a little bit different saying: >>hey here is access to GCP. knock yourself out until we get the bill.<<"* - Kelsey Hightower. [\[source\]](#). In other words, the developers can view the platform team as the cloud provider instead of seeing GCP as their cloud provider. Everything the developers need is exposed through the abstraction provided by the platform team. [\[source\]](#)

This is also described in the security section.

## 9.5. Workload overview and infrastructure replicability.

One challenge big companies can have when their developers have direct access to the cloud resources is that cloud services get created and forgotten about. These resources may have been created by accident or just used for a quick experiment. Other reasons could be that the resource is irrecoverable because the Terraform state was lost. The company ends up being charged for these un-utilized resources each month, because the company lacks the knowledge if the services are actually used or not. Tools like Crossplane and ArgoCD can limit or mitigate this risk.

ArgoCD has a feature to display all "orphan" resources that is not handled by ArgoCD (meaning it is no longer or never was checked into git). This is great for getting an overview of resources stored as infrastructure as code. Finding these cases can be essential in eliminating a false sense of security of the system being re-creatable should it go down.

If these cases are not detected you may think for that you can re-create your production cluster without any issues, but in reality your services depend on a resource that was created manually and

never checked into git.

Having a `core cluster` that functions as a control plane for the rest of your infrastructure helps you go from *Pets to Cattle*. The easier it is to spin up new cluster the less we will treat our infrastructure as "pets" [\[source\]](#).

## 9.6. Bootstrapping Problem

Every automatic process requires some manual task to start the process. This initial task/command can not be declarative, since a command by definition is imperative.

In order to simplify the setup-process as much as possible, we aim to make the bootstrapping as simple, clean and error-safe as possible. The only bootstrapping done in this implementation is setting starting a cluster (used as `core-cluster`) and then installing ArgoCD on it. The rest of the setup is handled automatically by ArgoCD with declarative/eventual consistency approach.

The bootstrapping done in this implementation does not touch logging, monitoring, ingress, crossplane-related-stuff, helm-charts, etc, which you could be forced to install sequentially through an imperative script.

The main point is that we can't remove bootstrapping entirely - but we can try to reduce it as much as possible. We would argue that this bootstrapping is fairly minimal, since it only does 2 steps. 1: Spin up core-cluster (locally or on cloud provider), 2: install and setup ArgoCD.

## 9.7. Streamlining your codebase

The setup described in this paper is built only using 2 file types: `.yaml` and `makefiles`. `.yaml` is used for declaring the state of the whole setup. Everything declared as *Infrastructure as Code* and checked into git (*GitOps*) - while `makefiles` are only for the initial bootstrapping.

"Since Crossplane makes use of Kubernetes, it uses many of the same tools and processes, enabling more efficiency for users - without the need to learn and maintain entirely new tools" [\[source\]](#). This creates an extremely streamlined infrastructure, because it does not require knowledge about e.g. Terraform, Ansible, or multiple scripting languages. I will consider this a huge benefit of this setup.

## 9.8. Limitations

### 9.8.1. Lack of providers | Early days | Maturity level



Currently, the biggest limitation of using crossplane is the lack of providers and feature set each provider provides.

When using kubernetes as a universal control plane for all of your infrastructure you rely heavily on the stability and flexibility of the controllers made by big cooperations or open-source communities.

When you use ArgoCD you put all your faith in that its controller correctly deploy your services and does not randomly delete arbitrary pods. When you use Crossplane you rely on the controller/providers correctly provision the requested resource and managing their lifecycle correctly. You as a user of these control plane this is out of your hands and you rely sole only the tools. This is the same limitation that Terraform has. Terraform is only as good as the providers that integrate with Terraform.

### **We observed some issues when working with ArgoCD and Crossplane:**

- Digital Ocean's provider can not delete resources on their platform. This means crossplane can only be used to spin up e.g. databases and kubernetes clusters - but not delete them afterwards. This partially removes the purpose of crossplane. This is obviously not intentional, and will probably be fixed in the near future. Overall this is just an example of providers not being mature and ready for control planes like crossplane.
- ArgoCD can not natively deploy resources when the generated yaml-files gets too large (as described here : <https://github.com/argoproj/argo-cd/issues/8128>). This is completely out of your hands. So if you want to deploy certain helm-charts that generate long yaml files then you instead have to find a custom workaround online or deploy it manually. This can be quite painful, since if ArgoCD cant deploy *every single resource* declared in your infrastructure its usefulness is greatly reduced.
- Crossplane will not generate/retrieve/store the kube-config in the core-cluster if the workload-cluster already exists when asked to spin up a workload-cluster . This means that if i delete the core-cluster and start a new one, the kubeconfig for each workload-cluster created are not stored on the new core-cluster and effectively lost. This can be fixed by just pulling the kubeconfig down manually with `gcloud -cli` and pushed into the core-cluster , but this is an undesirable error-prone workaround. I cant figure out if this is intentional by crossplane (maybe because of some security concern) or it just a bug/not-yet-implemented-feature. This is unfortunate, because if we can't delete the core-cluster then we still have a state/backup in this setup that we need to store somewhere (just like Terraform).
- ArgoCD can not connect to a external cluster based on data stored as a secret in kubernetes. Argo can only connect to external clusters by running `argocd add cluster <context-name-found-in-kubeconfig>` on your machine. This goes

against the idea of declaring everything in yaml by forcing the user to call a shell command manually. (described here:<https://github.com/argoproj/argo-cd/issues/4651>)

## 9.8.2. Multiple core-clusters

Running multiple instances of a `core-cluster` s at the same doesn't work well. You can easily spin up multiple `core-cluster` s at the same time. E.g. running a `core-cluster` on GCP and running one locally. The problem is that they each have their own internal desired state and may work against each other. One cluster may want to create a given resource on a cloud provider, while another may want to delete that resource. This results in race-conditions and unpredictable behaviour.

So the next question is how you test a configuration for the `core-cluster` if you can't spin up a new one, without it competing with the current version running. The only way to allow multiple `core-cluster` s to be run simultaneously is to run a complete copy of all your resources. So the copy could be named `core-cluster-copy` which then created e.g. a `prod-cluster-copy` and `aws-database-copy` and so on. It is fairly straight forward code-wise, so it is doable, but this would effectively double your cost infrastructure cost if you wanted to to a proper test of the `core-cluster` .

//insert image maybe //

## 9.9. Eliminating state?

When spinning up a cluster we don't have the hassle of first storing the state (and all the setup required in that process) in a shared location. This means the process of getting cloud resources up and running is faster, than by using Terraform. This lowers the *barrier of entry* and can be considered an improvement compared to using Terraform.

Furthermore Terraform requires that you store the state in some shared space for developers to use, and you need to manage the permissions to this shared space. By switching to crossplane the state is now accessible through kubernetes which the developers already have access to. In that sense i would consider crossplane an improvement. This does not mean that developer now have access to all cloud resources, just because they have write permissions to kubernetes. You can still set permission based on different namespaces/UserAccounts by using the abstraction layers created with Composite Resources (as explained in the *Platform Engineering*-section). This way you can still have fine granted access to different cloud resourced based permissions in kubernetes.

# 10. Conclusion

The golden hammer approach

# 11. References

Why git?

[https://www.youtube.com/watch?](https://www.youtube.com/watch?v=I5pVzP6wsP0&ab_channel=CNCF[CloudNativeComputingFoundation])

[v=I5pVzP6wsP0&ab\\_channel=CNCF\[CloudNativeComputingFoundation\]](https://www.youtube.com/watch?v=I5pVzP6wsP0&ab_channel=CNCF[CloudNativeComputingFoundation])

<https://opengitops.dev/>