Partition Balancing in Distributed Nested Data-Parallel Systems

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Abstract

Map-reduce frameworks such as Apache Hadoop and Spark provide the abstraction of a large, flat array that is processed in parallel across many machines. While this simple programming model has enabled the broad adoption of data-parallel distributed frameworks, these systems cannot express irregular parallel computation, and their performance is impacted by data imbalance across nodes. In this paper, we present a distributed framework for implementing *nested data parallel* (NDP) computation. Unlike previous NDP systems described by Blelloch and Bergstrom et al. that relied on the use of a *flattening* transformation at compile-time, we present a cost model that is used to select between multiple partitioning strategies at run-time. Through this, we provide a user-tunable means for trading node-to-node imbalance versus communication when executing distributed NDP programs.

1. Introduction

The use of map-reduce as a flat data-parallel (FDP) programming model for distributed systems has grown rapidly since it was introduced in Google's seminal 2004 paper [8]. The development of the open-source Apache Hadoop system enabled the use of this programming model outside of Google. Modern map-reduce systems such as Apache Spark [13] have refined the programming model further by reducing the dependency of the framework on disk via in-memory caching. While this refinement has enabled the use of map-reduce for iterative workloads, the programming model remains confined to computation that can be expressed via flat data-parallel operations. Specifically, Spark presents users with the abstraction of a resilient distributed dataset (RDD), which appears as a flat array that is distributed across compute nodes in a cluster [12].

To expand the algorithms that could be expressed as a data-parallel computation, Blelloch introduced the nested data-parallel (NDP) model [6]. In this programming model, users are provided the abstraction of an array whose elements are a nested level of arrays and data-parallel operators are applied on the nested arrays. A primary complication in the implementation of the NDP model is that the nested arrays frequently do not have uniform size. Several approaches have been suggested for balancing work in NDP programs, including the compile-time vectorization of NDP programs for execution on single-instruction multiple-data (SIMD) machines [6, 7] and flattening for multiple-instruction multiple-data (MIMD) machines [3]. Additionally, dynamic work-stealing approaches have been implemented [4].

In this paper, we introduce a distributed programming framework for NDP algorithms. Our implementation is built on top of Apache Spark. We track the structure of the nested arrays at runtime and choose between two strategies (*uniform* and *segmented*) for partitioning data across machines based on the estimated cost of each strategy. In the segmented partitioning strategy, all values in a single nested segment are co-located on a single compute node, and most computation can proceed without communication. The uniform strategy provides perfect load balance across all nodes, but many operations will need to communicate to execute. To choose between these strategies at runtime, we provide a cost model that evaluates the performance tradeoff of communication overhead versus node-to-node imbalance. Since the partitioning strategy is chosen at runtime, we can leverage knowledge of the nested array structure.

This work introduces the following contributions:

1. We introduce a dynamically scheduled distributed method for implementing NDP algorithms that is amenable to "cloud computing" platforms.
2. We demonstrate that the current best-known `scan` algorithm has $O(\frac{n \log p}{p})$ performance on bulk-synchronous systems, and provide a "block-parallel" relaxation of the `scan` operator that has $O(\frac{n}{p})$ performance.
3. We demonstrate a model-based approach for balancing partition load in distributed systems.

2. Background

2.1 Data-Parallel Programming Models

In data-parallel frameworks, all of the elements of a dataset are processed individually in parallel. These

2.2 Data-Parallel Distributed Computing

This work builds upon the infrastructure provided by the Apache Spark distributed data-parallel computing framework [2, 13]. Spark was designed for "cloud computing" platforms, where machines may be unreliable, and where network performance may preclude the use of traditional distributed message passing systems such as the Message Passing Interface (MPI). Unlike Apache Hadoop, where data is shuffled to/from disk between all processing stages [1, 11], Spark has an in-memory processing model. The in-memory processing model leads to large ($100\times$) performance for iterative jobs implemented using Spark instead of Hadoop [13].

Spark's programming model is implemented on top of the *resilient distributed dataset* (RDD) abstraction [12]. The RDD ab-

straction presents a view of an array which is chopped into *partitions* that are distributed over the computers within the Spark cluster. Programs enqueue data-parallel transformations on the Spark master, which are then interpreted into a directed-acyclic graph (DAG) for execution; this approach is similar to the DAG scheduling approach pioneered in Dryad [10]. Spark executes the DAG whenever a disk shuffle is required, or if a newly enqueued operation would create a cycle in the DAG (i.e., an iterative computation is scheduled).

To execute a stage, the Spark master serializes the user defined function (UDF) which is being applied, transmits this function to all worker nodes, and then applies the computation. While the general application programming interface (API) that Spark provides is data-parallel across all elements, the API transformations are implemented by applying the transformation iteratively across all elements of a partition—Spark also exposes this parallel-by-partition interface via the `mapPartitions` call. If data must be moved between partitions after an execution stage, a disk shuffle will occur. Disk shuffles are analogous to an execution stage with interleaved computation and all-to-all communication followed by a barrier before the next stage. This process is similar to how the results of `map` phases are moved to reducers in both MapReduce and Hadoop [8]—the main distinction is that Spark allows successive `map` phases, and that shuffles do not occur after all stages.

3. Implementation

3.1 Characterizing and Modeling Imbalance

3.2 Partitioning Strategies

3.3 Block-Parallel Scans

The `scan`[1] operator is challenging to implement in parallel, as the scan operation on array element a_n depends on the values of all elements $a_0 \dots a_{n-1}$. For clarity, we reproduce the definition of a `scan` given by Blelloch [5] here:

Definition 1. The `scan` operator takes an associative operator $\oplus$, and an ordered set of n elements:

$$[a_0, a_1, \dots, a_{n-1}]$$

and returns the ordered set:

$$[a_0, (a_0 \oplus a_1), \dots, (a_0 \oplus a_1 \oplus \dots \oplus a_{n-1})]$$

Blelloch proposed a parallel algorithm for computing vector scans [5]; this algorithm has recently been implemented for graphics processing units (GPUs, [9]). This algorithm is composed of two basic steps:

1. First, perform an "up sweep" by performing a parallel tree-reduction across the vector.
2. "Down sweep" by shifting in the identity value and rotating the tree elements.

A detailed description of this algorithm, as well as a proof of correctness is presented by both Blelloch [5] and Harris [9]. This algorithm completes in $O(\frac{n}{p} + \log p)$ time when evaluating a vector of n elements on p processors. For $n \gg p$, the runtime is approximated as $O(\frac{n}{p})$. Despite the efficient runtime, the *up sweep, down sweep* algorithm has several drawbacks:

- For a vector of type T, the $\oplus$ operator is restricted to $T, T \mapsto T$. This is an unnecessary restriction if we loosen definition 1 to include an additional input variable b_0, which is the additive identity value. If b_0 has type U, this allows $\oplus$ to become $U, T \mapsto U$. We include this in our updated definition 2.
- The *up sweep, down sweep* algorithm only has $O(\frac{n}{p})$ runtime for parallel random access memory (PRAM) compute models. As described in §2.2, MapReduce computing systems provide a block synchronous model. For this model, the runtime degrades to $O(\frac{n \log p}{p})$, as we have $\frac{n}{p}$ runtime for each of the $\log p$ stages in both the *up sweep* and *down sweep* stages.

To address the issues we have just presented, we introduce a block-parallel scan:

Definition 2. The block-parallel `scan` operator takes an associative *scan* operator $\oplus$ $(U, T \mapsto U)$, and an associative *update* operator $\otimes$ $(U, U \mapsto U)$, an identity value b_0, and an ordered set of n elements:

$$A = [a_0, a_1, \dots, a_{n-1}]$$

The ordered set A is partitioned into p ordered partitions:

$$\begin{aligned} P^0 &= [a_0, a_1, \dots, a_{\frac{n}{p}-1}] \\ P^1 &= [a_{\frac{n}{p}}, a_{\frac{n}{p}+1}, \dots, a_{2\frac{n}{p}-1}] \\ &\dots \\ P^{p-1} &= [a_{(p-1)\frac{n}{p}}, a_{(p-1)\frac{n}{p}+1}, \dots, a_{n-1}] \\ A &= P^0 \cup P^1 \cup \dots \cup P^{p-1} \end{aligned}$$

For notational convenience, we assume that $n \bmod p = 0$.

For all $P^k, k \in \{0, \dots, p-1\}$, we compute intermediate *block pre-scans* S^k where:

$$\begin{aligned} S_0^k &= b_0 \\ S_i^k &= S_{i-1}^k \oplus P_{i-1}^k, \forall i \in 1, \dots, p \end{aligned}$$

Note that all sets S_k have size $p+1$, not p.

For all $S^k, k \in \{0, \dots, p-1\}$, we then collect the S_p^k terms into set C, where $C_k = S_p^k$. We then perform the *update* phase across all S^k:

$$\begin{aligned} u^k &= \begin{cases} b_0 & \text{if } k = 0 \\ C_0 \otimes \dots \otimes C_{k-1}, & \text{otherwise} \end{cases} \\ U_i^k &= u_k \otimes S_i^k, \forall i \in \{1, \dots, p\} \end{aligned}$$

We return the ordered set:

$$\begin{aligned} S &= U_0 \cup U_1 \cup \dots \cup U_{p-1} \\ S &= [b_0 \oplus a_0, \dots, b_0 \oplus a_0 \oplus \dots \oplus a_{\frac{n}{p}-1}, \dots, \\ &\quad (b_0 \oplus a_0 \oplus \dots \oplus a_{\frac{n}{p}-1}) \otimes (b_0 \oplus a_{\frac{n}{p}} \oplus \dots \oplus a_{2\frac{n}{p}-1}) \otimes \dots \\ &\quad \otimes (b_0 \oplus a_{(p-1)\frac{n}{p}} \oplus \dots \oplus a_{n-1})] \end{aligned}$$

It is not possible to generally prove that the `scan` operator is equal to the block-parallel `scan` operator for all general $\oplus$ operators. However, it is straightforward to prove equivalence for some common operators. For example, given $T = U =$ integer, and $\oplus = + = \otimes$, it follows that $b_0 = 0$. In this case, all of the b_0 terms drop out, and $\oplus = \otimes$, therefore the block-parallel `scan` operation matches the `scan` operation.

Both the per-block *pre-scan* and the *update* operations from definition 2 have runtime $O(\frac{n}{p})$. On the computing platforms we are targeting, the cost of collecting a small amount of data from each partition is negligible. Therefore, the block-parallel `scan` has runtime $O(\frac{n}{p})$. We are able to use the block-parallel `scan` algorithm to perform efficient parallel `scans` across all datasets, and to accelerate segmented scans when using the `uniform` partitioning strategy introduced in §3.2.

[1] The `scan` operator is also known as the *all-prefix sum* [5].

4. Performance

5. Discussion

6. Conclusion

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