

# Lightweight Record-and-Replay for Intermittent Tests Failures

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## Abstract

In this paper we present lightweight record-and-replay (RR). In contrast to traditional “fully deterministic” RR solutions, lightweight RR focuses on handling nondeterminism arising from thread communication for programs with concurrent, message-passing architectures. By decreasing nondeterminism in programs, lightweight RR decreases the number of intermittent failures in program’s test suites. We evaluated the effectiveness of lightweight RR on Servo, a highly concurrent web browser. Our evaluation shows lightweight RR is effective at greatly reducing intermittent failures for some tests, but not others. Lightweight RR performance overhead remains a work in progress, but log sizes are quite small. We believe with further work lightweight RR could prove useful for lowering nondeterminism in programs at a negligible performance overhead.

## 1 Background

### 1.1 Concurrent Message Passing Channels

Slowdowns of single-core year-to-year performance gains in computing systems have given rise to the need for highly concurrent systems that take advantage of multiple cores, now available in all machines. Concurrent systems are normally implemented using a thread plus shared-memory, using locks to enforce exclusive writes to memory. This type of systems make it difficult to reason about useful properties of concurrent programs: data race freedom and deadlock avoidance. Furthermore shared data and the locks that protect it are often logically decoupled. That is, grabbing a lock before accessing data is not enforced by the programming language or runtime. Instead, in the worst case, it is merely a programming convention buried in the documentation, or at best, enforced through the code API and encapsulation.

An alternative concurrency model popularized by languages like Go, Erlang, and Rust has arisen: message passing through channels. With message passing, isolated threads or processes communicate via channels, sending data as messages to each other. This avoids the need for the programmer to worry about data races, memory consistency models, or other low-level details. Furthermore channels come in many flavors: bounded, unbounded, blocking, non-blocking, and more. Channels can be implemented using shared memory, with lock or lock-free queues. Channels have comparable performance to the lock and shared memory approach.

## 1.2 Intermittent Failures In Servo

Servo is a parallel browser engine with the goals: highly concurrent, memory safe, and easily embeddable. Servo achieves these goals thanks to its use of Rust: a novel systems programming language with stronger memory safety, data race freedom, and static guarantees. As well as featuring a concurrent message passing architecture. This allows Servo to be highly concurrent, maximizing parallelism, while maintaining its components decoupled.

Nondeterminism is inherent to concurrent systems. Servo is no exception. Adding to the challenges of programming parallel systems, debugging is more difficult than in sequential programs. This difficulty is further exacerbated by nondeterministic interleaving of threads.

Servo runs a large suite of browser-agnostic tests known as web-platform-tests (WPT) as part of the continuous integration system. WPT tests are expected to pass before changes to the code base are accepted. Unfortunately, Servo has hundreds of WPT tests that fail randomly for unknown reasons, known as intermittent failures. Since many intermittent tests seemingly pass or fail at random. There are unknown sources of nondeterminism in Servo which cause intermittent failures.

## 1.3 Existing Record-and-Replay Solutions

Record-and-replay has been widely studied in academia and used in industry. One such state-of-the-art system is Mozilla's **rr** project, which serves as a robust RR debugging framework. It is successfully used in production with code-bases consisting of millions of lines of code like the Firefox web browser. At a high-level, **rr** works by intercepting nondeterministic OS system calls and recording their values, as well as recording thread and process scheduling so later it can faithfully replay them. During replay, **rr** uses its log to replay the system calls with the same values seen during record, while dynamically handling scheduling to schedule threads and processes in the same order. **rr** can fully determinize any program, so it must record a large amount of information about an execution, so its record logs end up being quite large. Furthermore **rr** sequentializes execution of threads and processes, incurring particularly high performance overhead on parallel workloads.

While in principal `rr` is able to solve the problem with intermittent failures in Servo, we believe there can be a far more lightweight, high-level approach. `rr`'s implementation is OS dependent as it relies on many low-level OS details. Lightweight RR attempts tame some of the nondeterminism inherent to concurrent systems while operating at a much higher level: channel communication and thread scheduling. All while preserving parallelism in programs, and offering low overhead.

## 2 Lightweight RR

Lightweight RR records and replays multi-threaded systems where communication and coordination happens mainly through channel communication. Lightweight RR does not attempt to provide faithful full program record and replay. Instead, it lowers the amount of nondeterminism inherent to concurrent systems. This trade off allows lightweight RR several benefits: the implementation is far simpler than a full-fledged RR system, parallelism is maintained, only a tiny fraction of program execution is recorded making the implementation fast and the logs small.

Lightweight RR handles the following sources of nondeterminism:

- **Message arrival order.** While messages sent by a thread down a channel are guaranteed to arrive in FIFO order, multiple threads may be sending messages to the same channel simultaneously. Thus, message arrival order can vary.
- **Select operation.** Channel implementations often have a `select` operation. A `select` allows for receiving one or more message(s) from any channel with a message at the time of the operation, or blocking until a message arrives. Which messages are ready on a given select is timing dependent, so this is a nondeterministic operation.

Our approach is guaranteed to successfully replay an execution given that the above are the only sources of nondeterminism. If programs have nondeterminism outside the scope of lightweight RR, e.g. network communication, IO, thread locking, those programs may not replay successfully. If the replay execution diverges from the recorded execution, we say the execution has *desynchronized*.

Lightweight RR is robust to desynchronizations. When desynchronization is detected, the lightweight RR stops replaying the recorded execution and falls back to allowing the program to run natively.

### 2.1 Lightweight RR for Intermittent Failures

Lightweight RR is designed to work in the context of software tests with intermittent failures. Any test that nondeterministically return: unexpected results, timeout, or crash, can benefit from lightweight RR. First, we must capture a execution of the program with an “expected” results, this may take many tries

depending on the test. These “expected” logs are stored as part of the testing infrastructure. Later the tests run using lightweight RR in place of the standard channel library. The test run in replay mode where lightweight RR replays the “expected” execution. This allows lightweight RR to lower the nondeterminism and thus the number of intermittent failures for programs.

## 2.2 Supported Operations

For any message-passing channel implementation, we define the *receiver* as the reading end, and the *sender* as the writing end. We assume the channels are unbounded (do not have a maximum capacity), and may support multiple producers but a single consumer (MPSC). These assumptions fit the needs of most programs but nothing fundamentally stops us from supporting bounded, or multiple producers multiple consumer (MPMC) channels.

Lightweight RR supports all common operations on channels, including:

- **receive**: Block until we receive a message from a sender.
- **select**: Block on one or more receivers until one or more message(s) arrives from any channel.
- **try\_receive**: Non blocking variant of receive. If no message is available, an error is returned.
- **timeout\_receive**: blocks until a message arrives or the specified time elapses.
- **send**: non-blockingly send a message through a channel.

## 2.3 What is lightweight?

Lightweight RR does not reinvent the wheel by implementing deterministic channels from scratch, instead it is implemented as a wrapper around an existing channel implementation.

Furthermore, unlike fully deterministic approaches to RR, lightweight RR is implemented at the language-level as a user library, agnostic to the operating system and hardware details.

We highlight the following advantages between traditional RR methods and lightweight RR:

- Implemented as a language-level library, portable across operating systems and computer architectures.
- Threads run in parallel.
- Only channel communications events are recorded. No program data is recorded. Leading to smaller record logs.
- Robust to divergence of program execution during replay.

- The implementation wraps an existing channel implementation. Thus, the implementation is a straightforward transform.

## 3 Design

### 3.1 Assigning Deterministic IDs

In order to faithfully replay execution of a program, we must assign a deterministic thread ID (DTI) to all threads. DTIs must be unique and deterministic even in the face of racy thread spawning. Starting from the main thread, every thread spawn event is assigned an ID equal to the number of children that have spawned from this thread so far *child\_id*. A single counter per thread keeps tracks of this information. Then, a DTI is generated as a vector of *child\_ids* from the main thread, down to the new thread. The main thread has a DTI of `[]` (an empty list). As an example, the first thread spawned by the main thread is assigned a DTI of `[1]`, while the second great-grandchild of the main thread would have a DTI of `[1, 1, 2]`. Therefore, the length of a DTI is equal to the depth of the thread tree.

Analogously, every channel receiver/sender pair is assigned a unique, deterministic channel ID (DCI). The DCS consists of a `(DTI, N)`, where N is a per-thread counter, which is increased after generating a DTI.

DTIs are necessary for correctly replaying executions. Meanwhile DCIs are useful to detect desynchronizations, debugging, as well as understanding complex program interactions among threads, channels, and messages.

### 3.2 Recording Events

Given a channel message of type *T*, we transform it to a tuple `(T, DTI)`. Where DTI is the DTI of the thread who sent this message. That is, a thread now sends its DTI down the channel along with the message, this allows us to track which thread the message originally came from.

During record mode, we let the program run with as little changes to the execution as possible. When the program calls a channel function, we allow the function to go through, and merely record some information necessary for replay later.

For all channel communication events, we record:

- Event Id: A per-thread integer that increases by one on every channel communication event. This should be thought of as the *logical time* that an event occurred at.
- Sender ID: The DTI of the sender of a message.
- Event Type: `send`, `receive`, `try_receive`, `select`, etc.
- Data Type: The type of data sent down the channel, e.g. string, integer, bool, etc.

- Channel Flavor: The channel variant for an event, e.g. `ipc-channel`, bounded channel, `crossbeam channel`, etc.
- Event Status: Possible return variant of an event (see more below).
- DCI: The ID(s) of the channel(s) involved in this event.

Notice our record log does not need to record the value of the data sent down the channel.

Event status are the possible return variants of an event. For example, `try_recv` may either: timeout, get a receive error, or successfully receive a value. In case of a success we record the DTI of the sender thread. The sender's DTI is important for faithfully replaying executions when there are multiple writers to the same channel.

Select operations have an ordering to their receiver set. Each receiver is given an index to its position on the select, based on the order in which receivers were added to the set. On select events, we record the index (or indices for multiple events) of the receiver(s) with messages ready. Since receivers on a select are themselves MPSC channels. We also record the DTI of the sender for all receivers which returned a message during a select.

Many of the items recorded above are not strictly necessary. Instead, they are useful for robust logging (debugging), and detecting desynchronizations of executions. For users interested in running lightweight RR in production environments, many of these values could be removed at build-time.

### 3.3 Replaying Events

While record mode tries to affect the program's execution as little as possible, replaying requires wrangling in the program to force it to execute the same as the recorded execution. We may have to block threads and execute multiple channel receives per single channel receive requested by the user. All these operations are not directly observable to the user, and lightweight RR always maintains correct semantics with respect to the underlying channel implementation. Therefore, any program that works with a channel implementation will work equally well with lightweight RR.

Using (Sender ID, Event ID) we can deterministically identify an event for any thread. For a given event, we consult the log to see what actions are expected for this event. We compare the event type, DCI, and channel flavor to ensure we are still synchronized with the execution. Otherwise, a desynchronization error is returned.

Next, we consult the event status. If the status was e.g. timeout, we don't bother doing the actual operation on the channel, and instead immediately return a timeout. Even if the event status indicates the event succeeded, we may still not do the actual operation. Instead, no matter the actual receive events e.g. `timeout_receive`, `try_receive`, we implement a `rr_recv()` as follows.

`rr_recv()` call the blocking `receive()` on the receiver directly. The blocking receive will eventually return a message of type (DTI, T). We compare the

received DTI against the expected DTI from the log. If they match, we have found the correct message to return. Otherwise, this event came from another thread, so we add it to a per-receiver buffer of messages. We loop on `receive()` until the correct event is found. Next time there is a call to `rr_recv()`, the buffer is first checked for the expected event before looping on `recv()`.

On `select`, we use the expected index/indices to retrieve the correct receiver(s) from the select set and call `rr_recv()` on each receiver. Notice `rr_recv` takes care of buffering all “wrong” messages from other senders, so the correct message is automatically returned.

We must be careful with our use blocking `receive()` as a desynchronization may cause the thread to block forever. See Section 3.5.

### 3.4 Running Off the End of the Log

When replaying an execution, it is common to fall off the end of the log. That is, there is no (DTI,  $N + 1$ ) event in the log. Missing log entries usually mean that either: the program did not reach this point of the execution during record, or a desynchronization has occurred.

The former can happen for programs that race between exiting and communicating through channels. While one could argue this a source of nondeterminism outside the scope of lightweight RR, doing so would render lightweight RR useless for many programs. Instead, we handle end of the log events by blocking the thread on a conditional variable (this simulates the behavior of the thread not reaching this event in the recorded execution). See Section 3.5 for details on when this conditional variable is notified.

### 3.5 Handling Desynchronizations

We handle desynchronization events robustly by continuing to execute in a best effort mode (See Section 7 for possible extensions). Once a desynchronization is detected, initial user input determines whether the program should error out or continue executing the program.

Programs desynchronize when there are sources of nondeterminism outside of what lightweight RR handles. For example network IO, timers, randomness, etc. These other sources of nondeterminism are outside the scope of this work. We expect many programs to have other sources of nondeterminism. So lightweight RR must be robust to desynchronization errors.

Once we detect that execution has failed. We switch from the replay method described above, to merely doing the operation the user has asked for. This allows us to continue the execution but with no determinism guarantees. We notify all threads blocked on the end-of-log conditional variable, this unblocks these threads and they continue running on desynchronization mode. Special care must be taken to flush any values buffered by our `rr_recv()` operation.

If a program replay desynchronizes, threads blocking on `receive()` may never return. To avoid deadlocks, we use `receive_timeout()` instead of `receive()` in the implementation of `rr_recv()`. If the timeout time elapses, we

consider this a type of desynchronization error and run the rest of the program in `desync` mode.

## 4 Implementation

We implemented lightweight RR as a Rust library `rr-channel`. Our Rust implementation wraps two popular Rust libraries for channel communication: `ipc-channel` and `crossbeam-channel` (it would be trivial to support the standard library channels as well). Rust does not have support for dependency injection or inheritance, so users must swap all instances of the channel library they are using to `rr-channel`. To make this process seamless, `rr-channel` exposes the exact same API as `ipc-channel` and `crossbeam-channel`. Therefore, the only change needed is editing the name of the dependency when it is imported.

We must assign DTI to all threads. So a user must also use our `rr-channel` thread spawn function to ensure the thread receives a DTI. A program may not always be able to use our thread spawn function: threads may spawn as in program dependencies outside the control of the user. `rr-channel` handles this case by giving these threads a `None` DTI. Events are still recorded and replayed for `None` DTI. However, if two threads, both with `None` DTIs are both writing to the same channel, we cannot distinguish these them, so the execution may not be deterministic. We print a warning to users if this case is detected.

It is straightforward for our `rr-channel` implementation to support any channel implementations as long as the underlying implementation supports one single channel operation: `try_receive()`.

## 5 Evaluation

For our evaluation, we integrate `rr-channel` into Servo. Servo is a highly complicated program featuring a fully concurrent, message passing architecture. Servo represents a high target for lightweight RR: as Servo uses many complicated channels, to send many messages among its multitude of threads. Therefore, Servo is the perfect platform to stress-test lightweight RR and get a proper sense on the limits of our approach.

Thanks to the design of `rr-channel`, lightweight RR integration was fairly simple. Even though Servo is split into many libraries, with dozens of decoupled components. One day's worth of work is enough to have Servo using lightweight RR channels everywhere.

### 5.1 Reducing intermittent failures

To test the effectiveness of our approach we compiled a list of WPT tests known to fail intermittently in Servo. Using Github API we fetched all GitHub Issues for Servo marked as `I-intermittent`. We found 417 unique intermittently



failing tests. We ran those 417 tests 100 times (baseline) to get the average number of times a test returned the following possible statuses:

- expected: The test returned an expected outcome.
- unexpected: The test returned an unexpected outcome.
- crash: Servo crashed unexpectedly while executing this test.
- timeout: The test timed out before returning.

Out of those 417 tests, only 43 displayed intermittent behavior. That is, they test would change from one state above to another. 9/43 never returned “expected” so they were ineligible for lightweight RR.

To test our lightweight RR solution. We looped on the remaining 34 tests until we captured an expected execution. 2 tests were discarded because we were unable to record an expected execution after 100 tries. Even though these tests returned expected at least once in baseline. Note for the 2 tests in the previous sentence, as well as the 9 tests that never returned expected we could have recorded their unexpected executions as well, if the user is less interested in recording the expected execution, and just wants more consistent test results.

The remaining 32 tests make up our experimental results. Using the expected execution logs, we ran these tests 100 times in replay using our modified Servo.

Figure 1 shows the results for our 32 tests. The results are not great, but promising. While lightweight RR does seem to improve results, modestly to greatly depending on the test, sometimes lightweight RR actually returns less expected results. Many tests also failed to run all the way and timed out every time, these represent the missing rr bars in Figure 1. See Section 6 for discussion and interpretation of this results.

## 5.2 Performance Overhead

Lightweight RR only records channel communication events, a tiny subset of information recorded by traditional RR methods. Therefor we expect performance overhead to be quite smaller than traditional solutions.

We timed the our 32 tests using Servo’s testing infrastructure reported elapsed time per test. The average time per tests is based off 100 executions of each test. Both baseline and lightweight RR were measured in this manner. Figure 2 represents these results. As can be seen in this graph, the performance is terrible. We have identified the possible source of slowdown and hope to rerun the experiments soon.

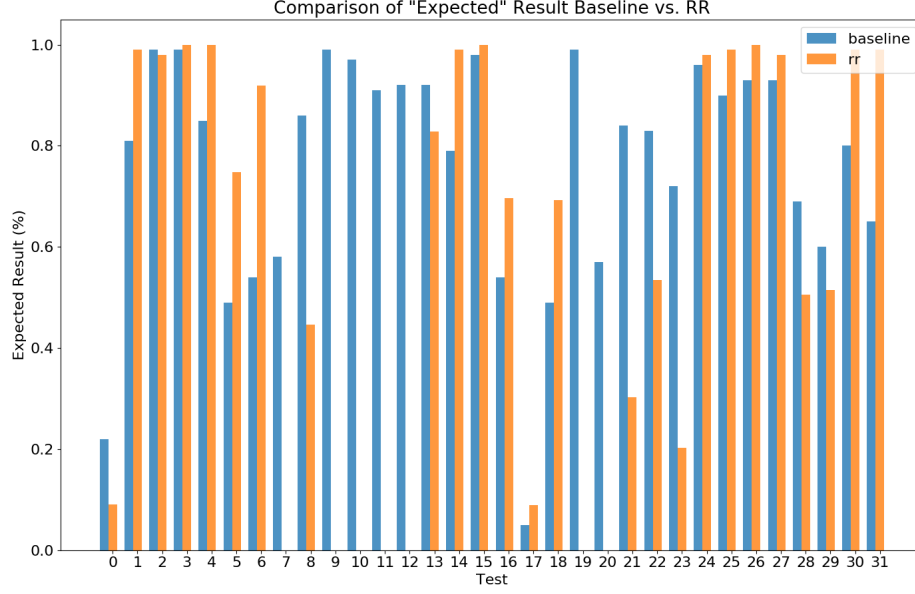


Figure 1: Results of comparing baseline with lightweight RR. Tests where rr is higher than the baseline represent cases where lightweight RR improved intermittent test's expected times. Missing orange bars represent a timeout during replay.

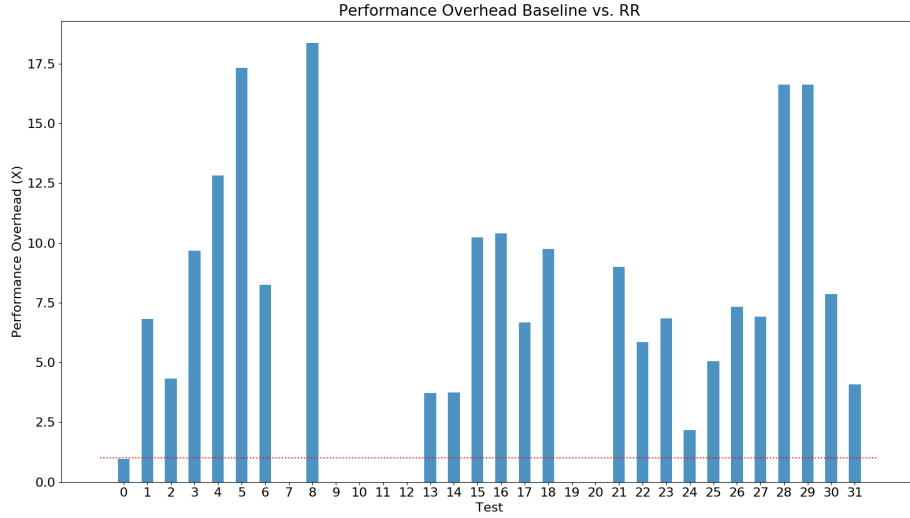


Figure 2: Performance of lightweight RR over baseline. Missing entries represent tests where rr-channels failed to run before timeout.

### 5.3 Space overhead

## 6 Discussion

The current evaluation results are disappointing to say the least. Here we discuss some of the reasons why lightweight RR does not work well in its current state.

Several tests failed to run all the way in replay mode, and instead timed out. We attribute these failures to logic bugs in the implementation. We believe, with further implementation effort, lightweight RR should never deadlock.

Servo is a complicated, highly concurrent program. Therefore, Servo represents a high mark to hit for lightweight RR. Simpler applications may fare better as far as lightweight RR is concerned.

Servo may be far too nondeterministic for lightweight RR to be useful: Servo may be desynchronizing early on, so the rest of the program runs without much benefits from lightweight RR. See Section 7 for proposed solutions to this problem. Servo has known sources of nondeterminism we are not capturing. Some examples include `rayon`, a library for high-performance data-parallelism. Since `rayon` threads are not spawned through our thread spawn wrapper, these threads are not assigned DTIs. Therefore any message which comes from a `rayon` thread cannot be properly determinized. We have observed such messages coming from `rayon` threads. With further implementation it should be possible to assign deterministic thread identifiers to Servo threads. Similarly, Servo uses `Tokio` library for asynchronous programming. Threads spawned through `Tokio` are not determinized. Even handling `Tokio` and `rayon` threads, Servo naturally has many nondeterministic IO operations. Network traffic, disk IO, and timers, all contribute to nondeterministic executions in Servo.

It may just be the case that Servo is too nondeterministic in its current state to benefit from our approach. Perhaps a combination of lightweight RR and some small modifications of Servo components may yield better results.

## 7 Future Work

The current work just barely scratches the surface: providing an implementation and doing a first attempt experiment. We believe with some iteration we could significantly increase how well lightweight RR works.

Lightweight RR has many possible extensions and future work. Currently, when the replay execution desynchronizes, we merely fall back to executing the program natively. A more elaborate desynchronization recovery scheme could be robust to some desynchronized events. Some threads could be desynchronized while other threads continue to run synchronized. Similarly, we could look at real synchronization recovery by attempting to match the execution back at a later point.

Once a desynchronization is detected, it is indicative of a source of nondeterminism in some program thread. Using the current execution, and the log, it

may be possible to help the programmer narrow down and identify the source of nondeterminism.

When we detect a desynchronization, we could start recording this alternate program execution. Later the two executions could be compared to better understand why they diverged. Furthermore, when considering continuous integration, and as programs evolve overtime, we expect changing part of the code will have changes in the execution, therefore, as new patches are tested for merging we could record the new executions, and use those for future record and replay testing.

The log we record is a full record of all communications and thread topology for a given execution. This log could create a visualization of threads, and channel communication for the program execution. This is extremely useful to a developer as a visualization tool to understand concurrent programs.

Servo is careful to use non-blocking, unbounded, channels. This helps Servo developers reason about deadlock-freedom, as long as there is no cycles in the communications among threads of Servo. Using the recorded logs, we could verify that cyclic dependencies don't exist for any given execution of Servo, thus increasing confidence in deadlock-freedom.

The evaluation is currently incomplete. More work is required to understand what kinds of applications or tests benefit most from lightweight RR (if any). Performance is also beyond disappointing, work is needed to understand performance implications of lightweight RR.

## 8 Conclusion

In this paper, we describe lightweight RR. A halfway point between heavyweight, fully deterministic systems, and no determinism enforcement. Lightweight RR is designed to empirically lower the amount of intermittent test failures in a program's test suite, while enjoying minimal performance overhead and record-log sizes. Lightweight RR has exciting and promising future work avenues beyond the just record and replay. With more work, lightweight RR could prove to be a useful tool for the development and debugging of concurrent systems.