

Synchronization

Physical clocks

Logical clocks



Summary so far ...

A distributed system is:

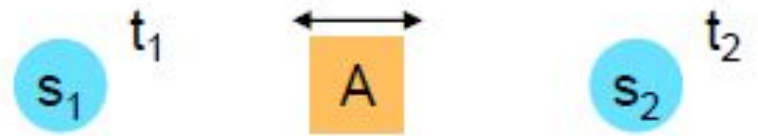
- a collection of *independent computers* that appears to its users as a *single coherent system*

Components need to:

- Communicate
 - Point to point: request-reply, RPC/RMI
 - Point to multipoint: multicast, epidemic
- Cooperate
 - Naming to enable some resource sharing
 - Naming systems for unstructured (flat) namespaces:
 - consistent hashing, DHTs
 - Naming systems for structured namespaces
 - **Event ordering**
 - **Synchronization**

An example

- Multiplayer game ...
 - Distributed implementations generally use replicated state: each player has its own view of the world.
 - Object **A** (the target) and the “world” are replicated as S_1 and S_2
- ... players shoot the same target at about the same time
 - Players shot at local times t_1 and t_2 on two replicas S_1 and S_2
- Who gets the points?
 - Need to aggregate events into one consistent view.



Issues: Correctness. Overheads. Fairness.

Room for application-specific solutions

Example: Replicated State Machine



Q: Do the updates need to be executed in the same order on the two replicas?

Issues:

- What kind of ordering: partial or total?
- Does 'real' (physical time) ordering matter for correctness?



Why event ordering is more complex than in a single-box system?

- No single physical clock
 - Likely multiple physical clocks,
 - Likely out of sync and drifting
- Need to aggregate a 'global' view
- Failures



What are your tools?

- Physical clocks
 - Provide [an estimate of] actual (real) time.
- 'Logical clocks'
 - Where only ordering of events matters
 - Lamport clocks
 - Vector clocks (ability to trace event dependence)



Keeping track of time easily gets complex ...

"Fifty-six standards of time are now employed by the various railroads of the country in preparing their schedules of running times"

-- New York Times, April 1883 [[source](#)]

Other Examples?

- The October with only 20 days (in 1582)
- Leap Second



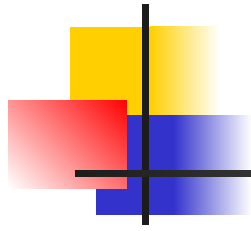
Physical clocks (I)

- **Problem:** Achieve **coordination on real time** in a distributed system
- **The standard: Coordinated Universal Time (UTC):**
 - Atomic clocks: Based on the number of transitions per second of the cesium 133 atom
 - accurate but expensive
 - Leap second from time to time to compensate for days getting longer.
- UTC is **broadcast** through short wave radio and satellite.
 - Accuracy $\pm 1\text{ms}$ (but if weather conditions considered $\pm 10\text{ms}$)
 - Needs a receiver



Problem:

- Suppose we have a distributed system with a UTC-receiver somewhere in it.
- How do we:
 - distribute time to each machine, and
 - maintain a bound on how much local time differs from actual time?



Internal mechanism (the “clock”) at each node

- Each machine has a *timer*
- Timer causes an *interrupt* H times a second
 - Interrupt handler adds 1 (a ‘*tick*’) to a software clock
- Software clock keeps track of the number of *ticks* since some agreed-upon time in the past.

Time is correct
Drift = 0

Clock does not deviate
Drift rate = 0

Clock drift and drift rate

Notation: Value of clock on machine p at real time t is $C_p(t)$

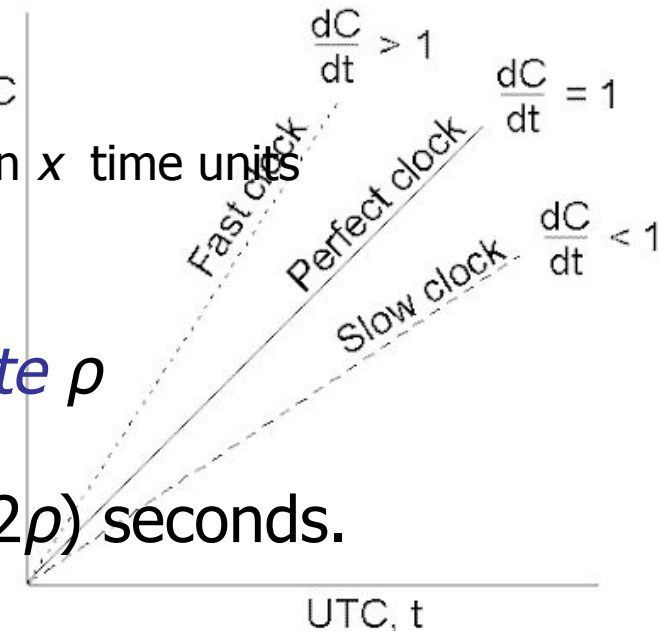
Clock drift: $|C_p(t) - t|$ **Drift rate:** $\frac{dC_p(t)}{dt} - 1$

Ideally: $C_p(t) == t$ $dC_p(t) = dt$

Goal: Guarantee on maximum drift
i.e., never let clocks on two nodes differ by more than x time units

How?

- Manufacturer guarantees max **drift rate** ρ
 $1 - \rho \leq (dC/dt) \leq 1 + \rho$
- Nodes synchronizes at least every $x/(2\rho)$ seconds.

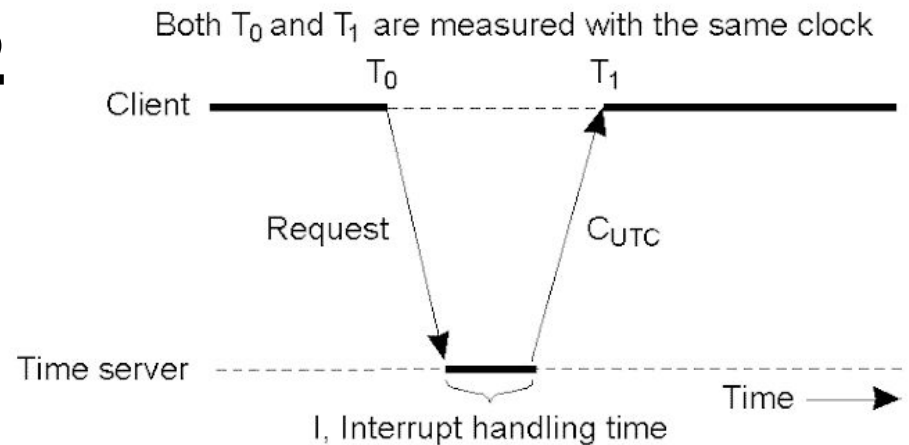


Building a complete system ...

- Every machine asks a **time server** for the accurate time at least once every $x/(2\rho)$ seconds

Client updates time to?

$$T_{\text{new}} = C_{\text{UTC}} + (T_1 - T_0) / 2$$



Q: Problems?

- Fundamental:** setting the time back is **never** allowed ☐ smooth adjustments.

Real world: Network Time Protocol (NTP)

- Stratum 1 NTP servers – receive time from external sources (cesium clocks, GPS, radio broadcasts)
- Stratum N+1 servers synchronize with stratum N servers and between themselves
 - Self-configuring network
- **Survey** (fairly old: 2006)
 - > 1M NTP servers
 - 0.2% of the NTP servers >128ms offset from synchronization peer
 - Excluding these: - median: 0.7ms
- mean: 7ms

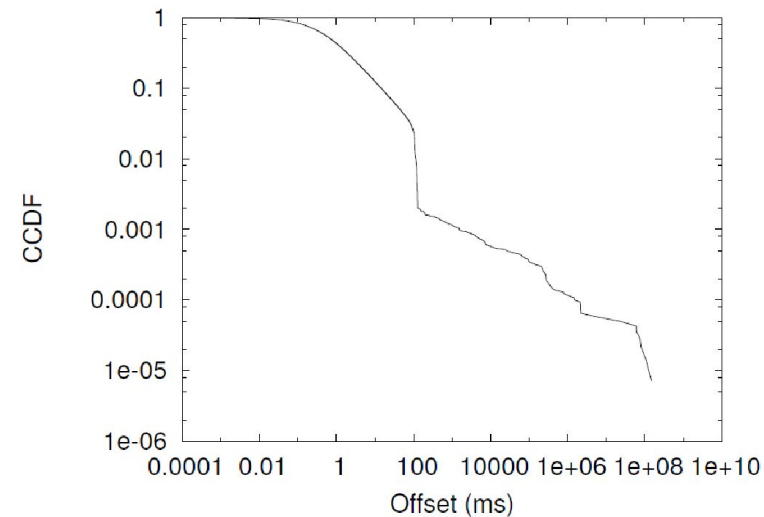
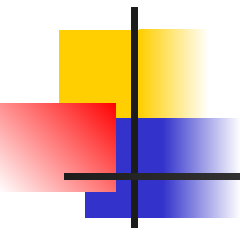


Fig. 1: CCDF of host-peer offsets



[Summary so far] Physical clocks

- Clock **drift**: time difference between two clocks
- Sources of errors (drift)
 - Variability in time to propagate radio signals. ($\pm 10\text{ms}$)
 - Clocks are not perfect: **Drift rates**
 - Network latencies are not symmetric
 - Differences in speed to process messages
- System design to limit drift
 - One node holds the 'true' time
 - Other nodes contact this node periodically and adjust their clocks
 - How often?
 - How exactly the adjustment is done?



- We've established that clocks can not be *perfectly* synchronized (and atomic clocks are costly).
- What can one do in these conditions?
 - Get a better estimate of time by using different technology
 - e.g., use GPS to obtain time in your system
 - Expose uncertainty and design the system to take drift into account
 - Example 1: Google's Spanner
 - Example 2: Server design to provide at-most-once semantics
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GPS – Global Positioning Systems Intro

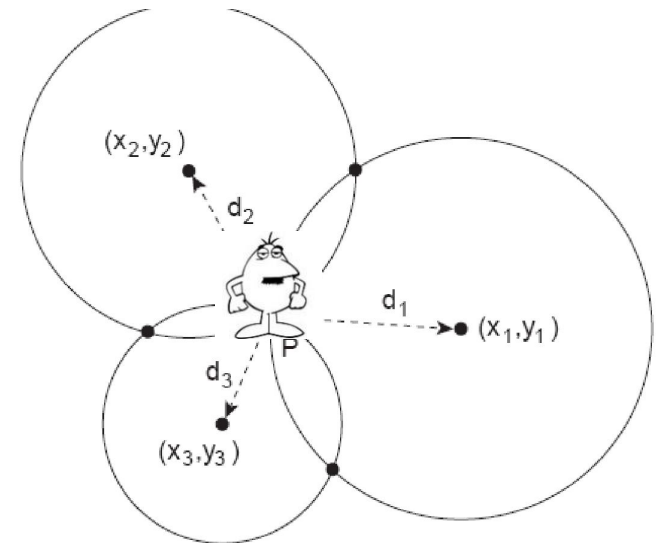
Basic idea: To estimate distance to a landmark (e.g., satellite)

- Estimate signal *propagation time* between you and the landmark
- Multiply by signal speed

Strawman: Assume that the clocks of the satellites and receiver are accurate and perfectly synchronized:

But, in real world:

- 3D not 2D
- The receiver's clock is definitely out of sync with the satellite



- Unknowns: x_r, y_r, z_r coordinates of the receiver.
- Known:
 - x_i, y_i, z_i coordinates of satellite i
 - T_i is the send timestamp on a message from satellite i
 - $\Delta I_i = (T_{\text{now}} - T_i)$ measured delay for message sent by satellite i
- **Distance** to satellite i *can be estimated*:
 - (1) Propagation time: $d_i = c \times \Delta I_i$
 - (2) Geometric distance:

$$d_i = \sqrt{(x_i - x_r)^2 + (y_i - y_r)^2 + (z_i - z_r)^2}$$

- 3 satellites \square 3 equations in 3 unknowns. I'M DONE!

- ... BUT: I assumed receiver clock is synchronized!

*the satellite has an atomic clock anyways so T_i is correct

- **Unknowns:** x_r, y_r, z_r coordinates of the receiver.
- **Known:** X_i, Y_i, Z_i - coordinates of satellite i
 - T_i - the send timestamp on a message from satellite i

$\Delta I_i = (T_{\text{now}} - T_i)$ propagation delay of message sent by satellite i

- **Distance** to satellite i *can be estimated:*
 - Propagation time: $d_i = c \times \Delta I_i$
 - Geometric distance: $d_i = \sqrt{(x_i - x_r)^2 + (y_i - y_r)^2 + (z_i - z_r)^2}$
- So far I assumed receiver clock is synchronized*!
 - What if it needs to be adjusted? $T_{\text{real}} = T_{\text{now}} + \Delta r$
 - $\Delta I_i = (T_{\text{now}} + \Delta r) - T_i$
 - Collect one more measurement from one more satellite!

*the satellite has a atomic clock anyways so T_i is correct



Two takeaways

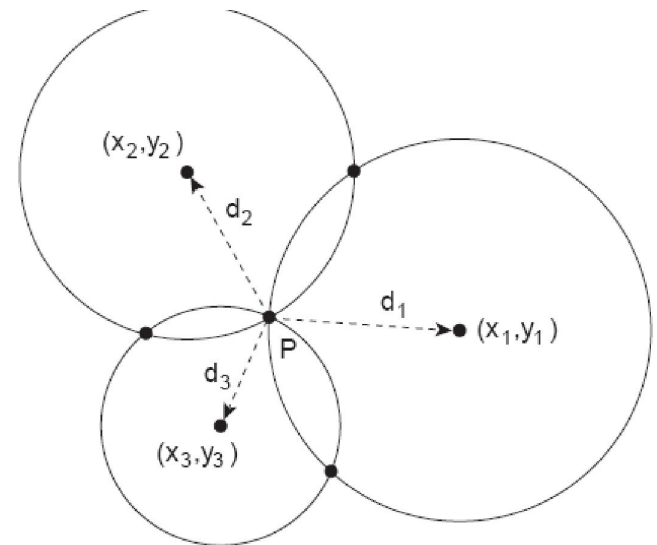
- (1) Triangulation technique
 - Can be used in other contexts: e.g., computing geographical position in wired networks
- (2) Enough information to correct the clock drift at the receiver

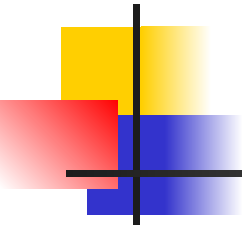
Similar triangulation techniques work in other contexts: Computing geographical position in wired networks

Observation: a node P needs at least $k + 1$ landmarks to compute its own position in a k -dimensional space.

Consider two-dimensional case:

Solution: P needs to solve three equations in two unknowns (x_P, y_P)

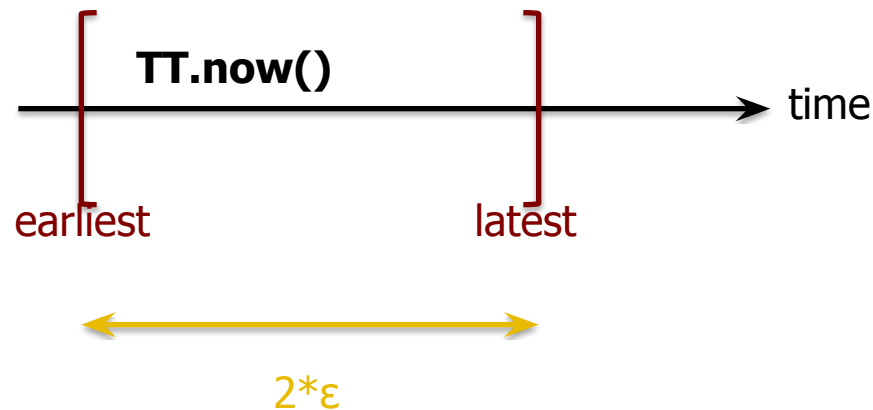




- We've established that clocks can not be *perfectly* synchronized (and atomic clocks are costly).
- What can one do in these conditions?
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Google's Spanner

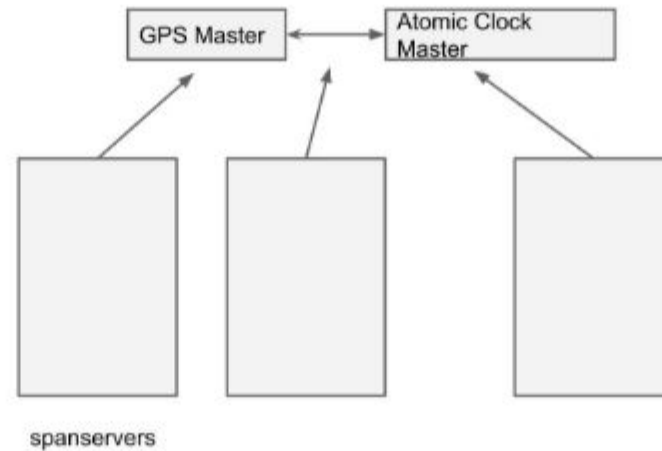
- “Global wall-clock time” with bounded uncertainty
 - Time estimate: $TT.now() \sqsubseteq [\text{earliest}, \text{latest}]$
 - Guaranteed interval



TrueTime implementation

Google

True Time: Architecture

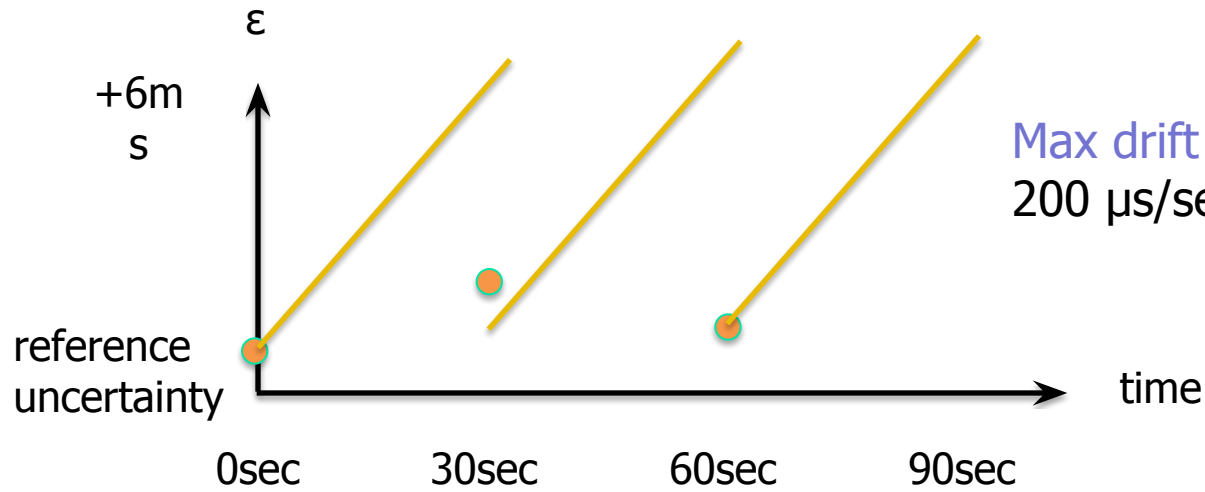


periodic poll: [earliest, latest]

In-between polls, uncertainty radius grows based on worst-case clock drift (200 usec / sec)



$\varepsilon = \text{reference } \varepsilon + \text{worst-case local-clock drift}$

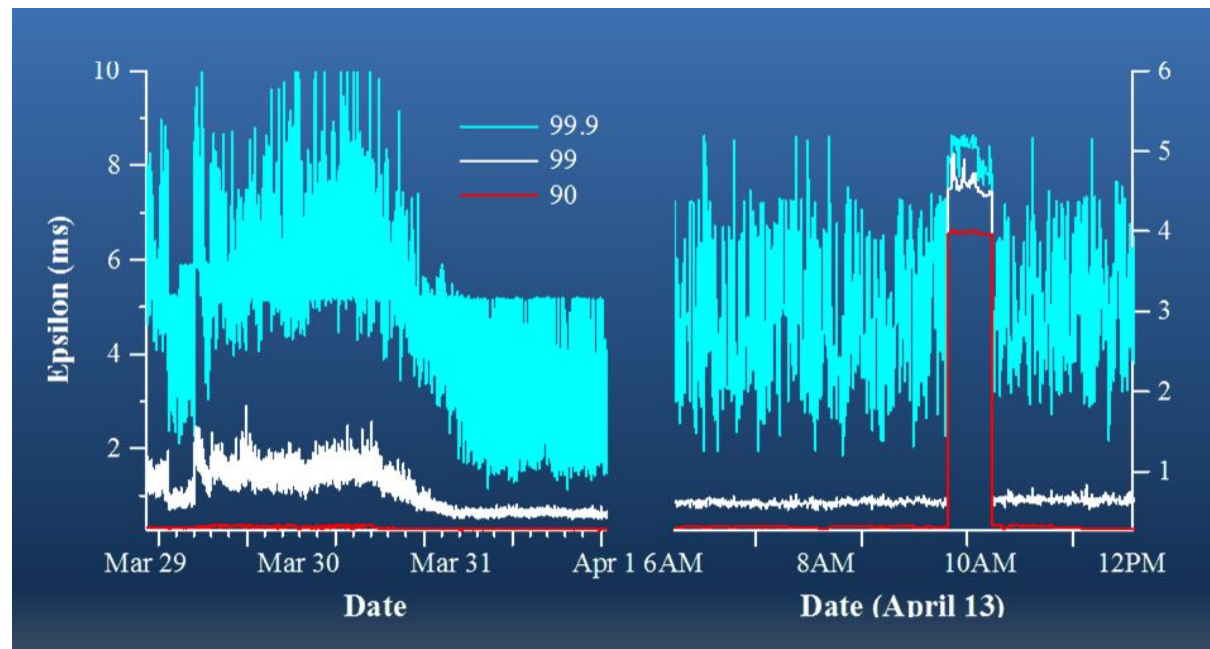


Max drift rate:
200 $\mu\text{s}/\text{sec}$

Max drift: 6ms
□ (for a 30s sync interval)

Practical Experience @Google

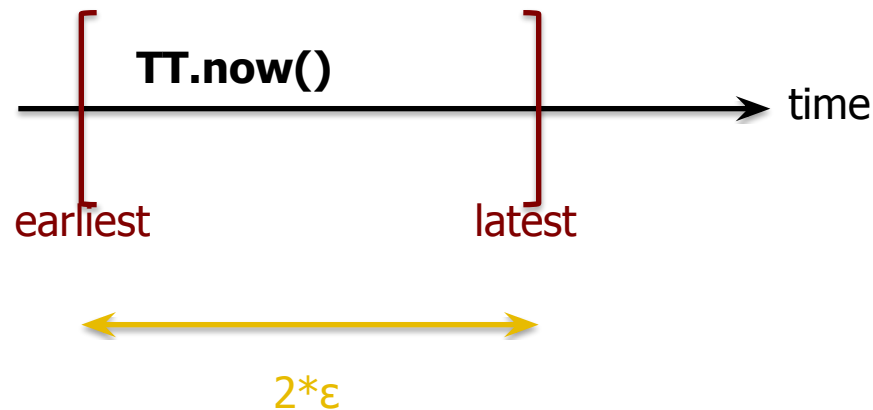
- (1) Is ε truly a bound on clock uncertainty?
 - Violations of guarantees [drift rate] unlikely: Bad CPUs 6 times more likely than bad clocks (based on 1y of data)
 - “As a result, we believe that TrueTime’s implementation is as trustworthy as any other piece of software upon which Spanner depends”
- (2) How bad does ε get?
 - Network-induced uncertainty



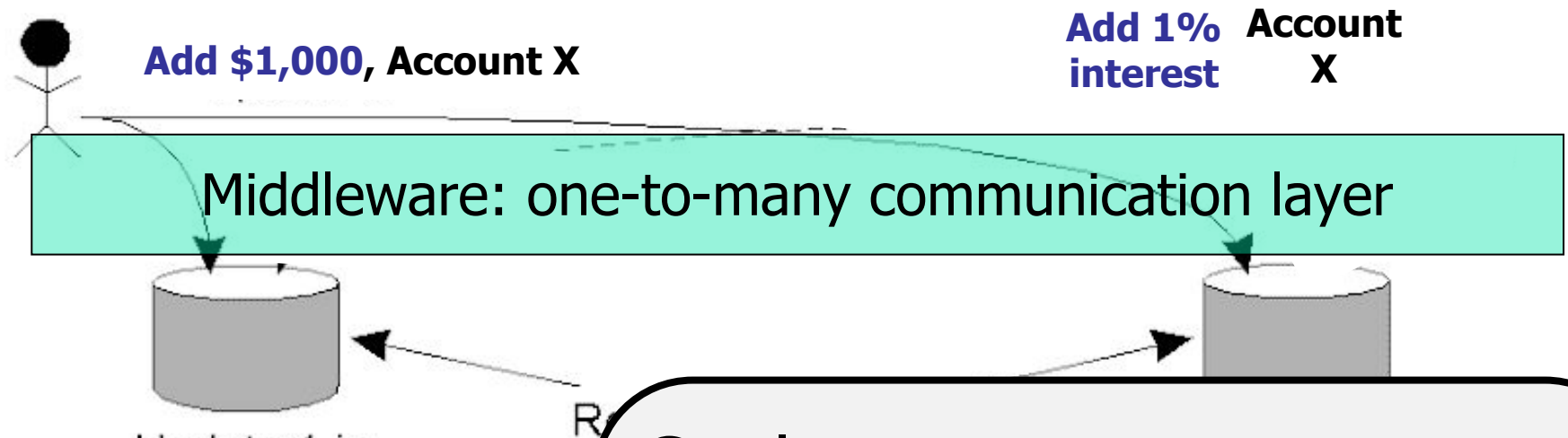
ε sampled at timeslave daemons immediately after polling the time masters

Recap: expose uncertainty of time estimates

- “Global wall-clock time” with bounded uncertainty
 - Time estimate
 - Guaranteed interval



How would Spanner/TrueTime help here



Q: Do the updates in the same order on the two replicas?

Issues:

- What kind of ordering is required?

- Does 'real' (physical time) ordering matter for correctness?

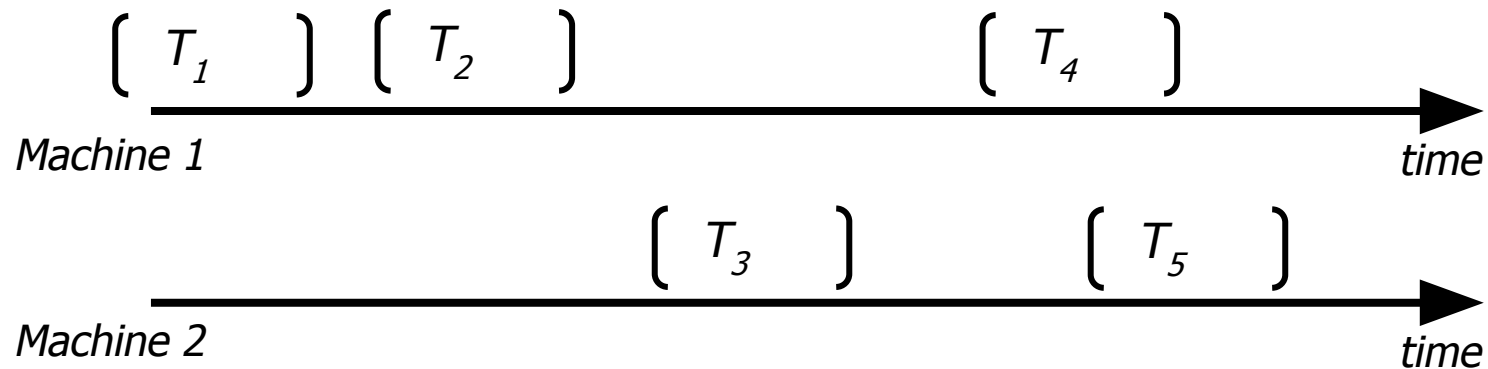
Goal (for next few slides):

aggregate data from transaction initiators to construct a correct ordering of events

[NB: This is a over-simplified view of spanner]

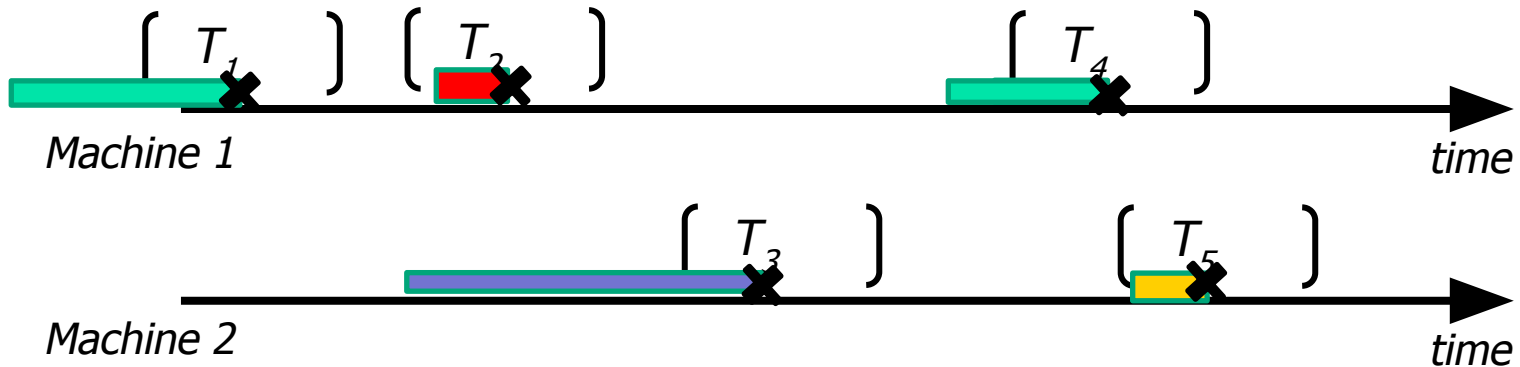


Ok – so how does this help with event ordering?



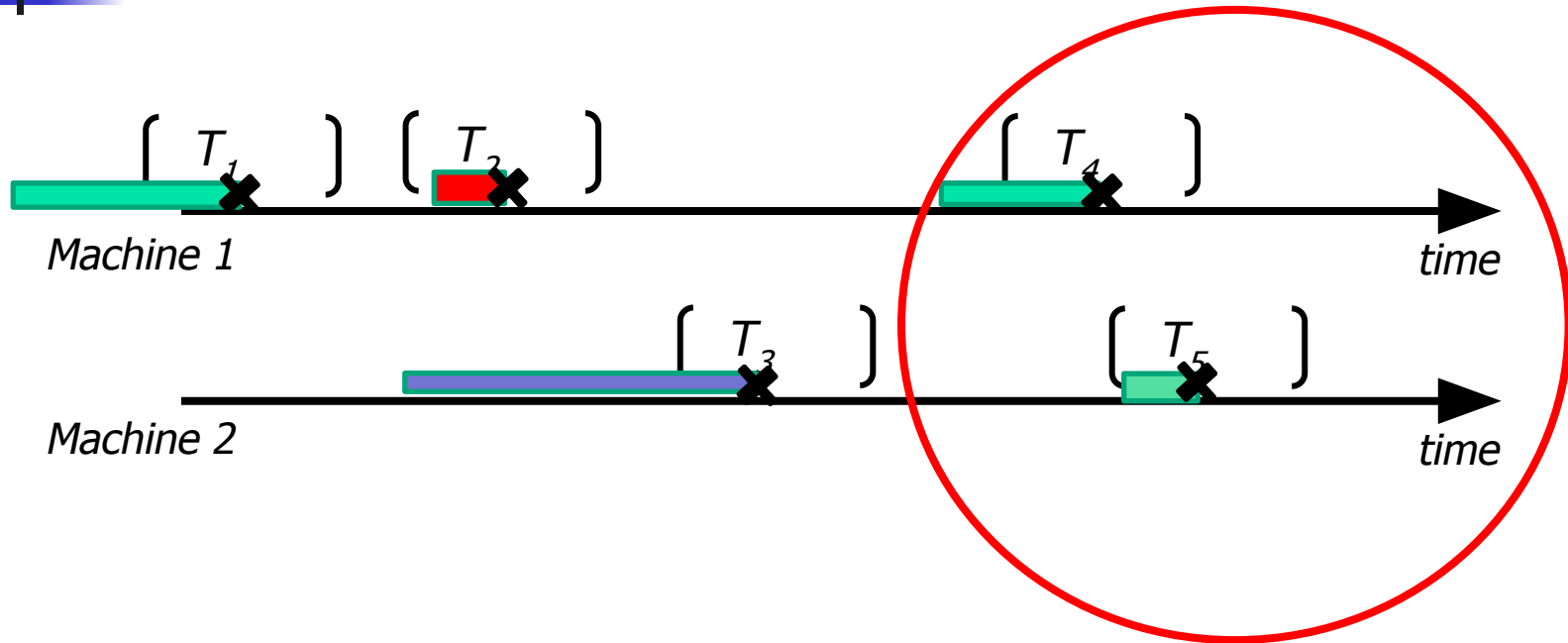
- Events get timestamped (with uncertainty intervals)
- Use the timestamps to recreate a global view for the order in which events occurred.
 - Order unambiguous as long as the uncertainty intervals do not overlap

Ordering transactions



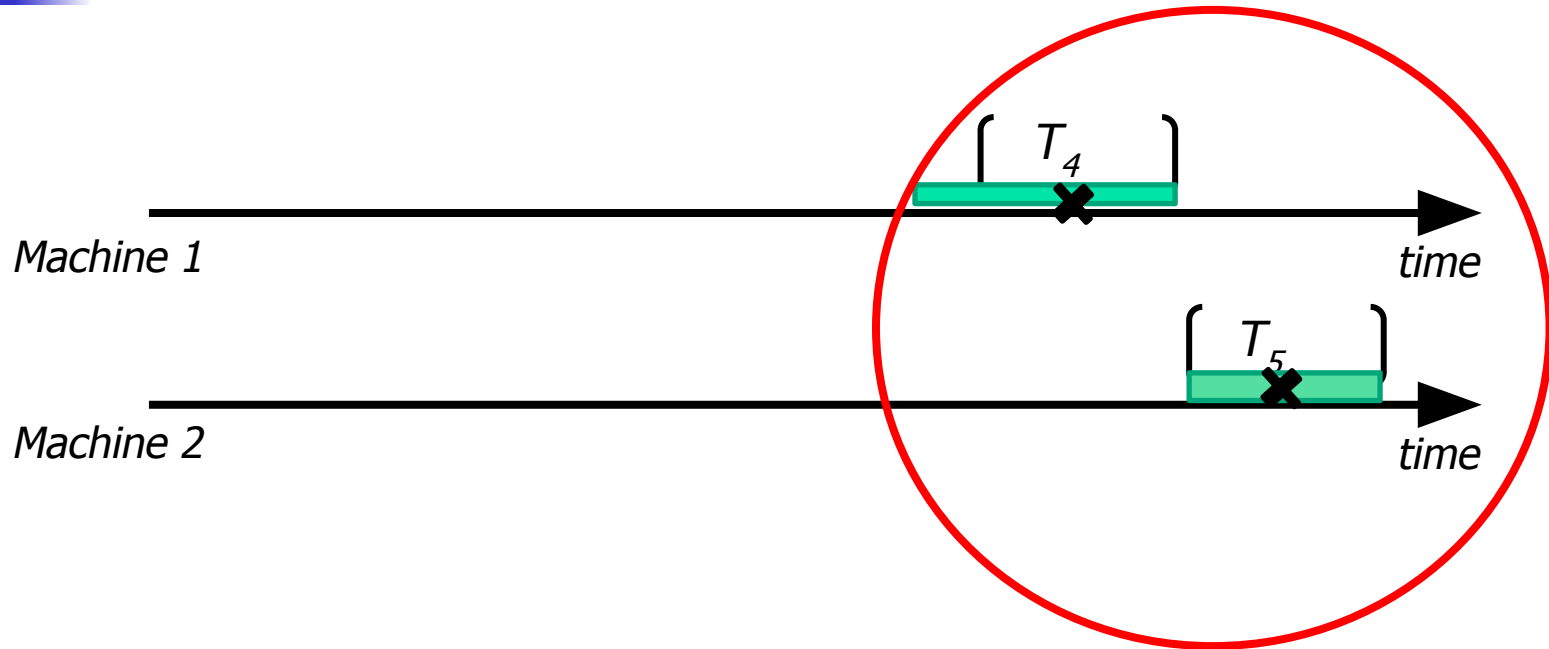
- Assume that T_x are transaction timestamps.
 - Timestamps taken at commit time
- Goal is to recreate the global transaction order
 - If two transactions are not conflicting: order does not matter
 - Else: need to get the order right

Ordering transactions

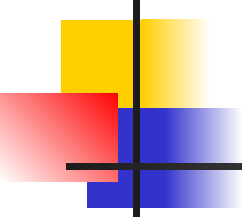


- Assume that T_x are transaction commit timestamps.
- Goal is to recreate the global transaction order
 - If two transactions are not conflicting: order does not matter
 - Else: need to get the order right

Spanner solution



- Move timestamp within the transaction
 - So that full uncertainty interval is within the transaction
- If needed (i.e., transaction is too short) extend the transaction
 - i.e., delay releasing the resources
- This way conflicting transactions have timestamps that can be ordered without uncertainty

- 
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- We've established that clocks can not be *perfectly* synchronized (and atomic clocks are costly).
 - What can one do in these conditions?
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 - e.g., use GPS to extract time in your system /
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Efficient at-most-once message delivery

Goal : Server has to identify previously served requests to implement at-most-once semantics

[Old] Assumptions:

- Message propagation time bounded
- Physical clocks not used
 - (so no need to make assumptions about drift rates)
- Client may resend messages for up to *MaxLifeTime*

Issues

- 1: For how long to maintain 'transaction' data?
- 2: How to deal with server failures?
 - (minimize the state that is persistently stored, when to restart)

Issue1: For how long to maintain transaction data at server?

■ Server's goals:

- 1. Identify message duplicates – **at-most-once delivery**
- 2. While trying to avoid storing too much state

■ Context:

- No bound on message propagation time
- Any two clocks in the system differ by at most *MaxClockDrift*
- Client may resend messages for up to *MaxLifeTime*

■ Mechanism idea: Server discards messages that have been generated too far in the past.

- **Client protocol:** client sends transactionID and **physical** timestamp
- Server computes: $G = T_{now} - MaxLifeTime - MaxClockDrift$
 - ... and maintains transaction data only for the interval $[G..T_{now}]$
- Discards messages with $msg_{timestamp}$ older than G
- Ignores (or delays) messages that arrive in future: $msg_{timestamp} > T_{current}$



Efficient at-most-once message delivery

Design goal : Server has to identify previously served requests to implement at-most-once semantics

[New] Assumptions:

- No bound on message propagation time
- There is a bound on clock drift
 - any two clocks in the system differ by at most *MaxClockDrift*
- Client may resend messages for up to *MaxLifeTime*
 - *after that reports error (timeout) to the application*

Issues

- 1: For how long to maintain 'transaction' data?
- 2: How to deal with server failures? What to persist across server failures? When to restart?
 - (minimize the state that is persistently stored, minimize downtime)



Efficient at-most-once message delivery (II)

- Issue 2: What to persistently store across server failures?
 - Strawman #1: Store nothing persistently.
 - Incorrect if server reboots quickly
 - Strawman #2: Persistently store ALL transactions.
 - Costly
 - Strawman #3: Store nothing persistently, and wait *MaxLifeTime* after reboot before starting to process messages
 - Correct but lowers availability.



Efficient at-most-once message delivery (II)

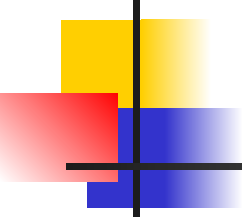
- Issue 2: What to persistently store across server failures?
- Towards a solution: need to approximate failure time
 - Write current time (CT) to disk every ΔT
 - At recovery read it
 - Failure time is approximated as G_{failure} from last saved CT
 - After recovery – when a new message arrives
(let's ignore clock drift for now and assume perfect clocks)
 - Discard messages with timestamp older than $G_{\text{failure}} + \Delta T$
 - Reason: the server might have seen these in the past (but lost the cache)
 - Process messages with timestamp newer than $G_{\text{failure}} + \Delta T$
 - Reason: surely not seen before failure

[Quiz-like question: Change the formulas to consider clock drift]



Quiz-like question

- Previous solution
 - no assumption on maximum message propagation time
 - uses physical clocks (with a bound on max clock drift)
- You can now assume an upper bound B on message propagation time
 - Design a solution that does not use physical clocks?

- 
-
- We've established that clocks can not be *perfectly* synchronized (and atomic clocks are costly).
 - What can I do in these conditions?
 - Get a better estimate of time by using new technology
 - GPS systems
 - Expose uncertainty / Design the system to take drift into account
 - Example: Server design to provide at-most-once semantics
 - Give up physical clocks!
 - Consider only event order - Logical clocks



Logical clocks -- Time Revisited

- What's important?
 - The precise time two events occurred?
- OR
- The order in which the two events occurred?

(1) Alice intends to quit her employer

- She removes her boss as a friend
- Posts *“I’ll quit tomorrow! Here is the story: ...”*
(visible to friends only)

Alice expects
her boss will
not be able to
see her post

(2) Bob, a friend of Alice,

- Reads Alice’s post
- Messages Charlie, a common friend:
*“Wow! Alice just posted that she’ll quit! Read her story!” **

(3) Charlie, a friend of both

- Reads Bob’s message
- Goes to Alice’s timeline to read the story

Charlie expects to
see Alice’s post

Common expectation: process
events in the order they occurred

* We are in 2003, post sharing has not been invented



Logical clocks: ROADMAP

Define partial order for events

"happens before"
relationship " \square "

What are the constraints?
What does 'ordering' mean?



Logical clocks

Assign timestamps to events
such that:

if $a \square b$ then $ts(a) < t(b)$

Come up with a system to 'label'
events that respects these constraints



Build systems

E.g., totally ordered
group communication

How is this used?



What are the constraints?

What does 'order' mean?

Need to introduce a **notion of ordering** (before we can order anything).

The **happened-before** relation (notation: " \rightarrow ") on a set of events in a distributed system

- if a, b are events in the same process, and a occurs before b , (in physical time) then $a \rightarrow b$
- if a is the event of sending a message by a process, and b receiving same message by another process then $a \rightarrow b$

Property: Transitive: if $a \square b$ and $b \square c$ then $a \square c$

Two events are concurrent if nothing can be said about the order in which they happened (i.e. happens-before is a **partial** order)



Logical clocks: ROADMAP

Define partial order for events

“happens before”
relationship

Notation: \square

What are the constraints?
What does ‘ordering’ mean?



Logical clocks

Assign timestamp to
events such that if $a \square b$
then $ts(a) < t(b)$

Come up with a system to ‘label’
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Build systems

E.g., totally ordered
group communication

How may this be used?



Logical clocks

Objective: Build a **view** on the system's behavior that is consistent with the 'happened-before' relation

Attach a timestamp $ts(e)$ to each event e , such that:

- **P1:** If a and b are events in the same process, and a happened before in physical time b , then we demand that $ts(a) < ts(b)$.
- **P2:** If a corresponds to sending a message, and b to the receipt of that message, then also $ts(a) < ts(b)$.

- **Problem:** How to attach timestamps to all events in the system (consistent with the rules above) when there's no global clock
 - maintain a **consistent** set of logical clocks, one per process.

Problem: Need to attach timestamps to all events in the system

- maintain a **consistent** set of logical clocks, one per process.
- there's no global clock

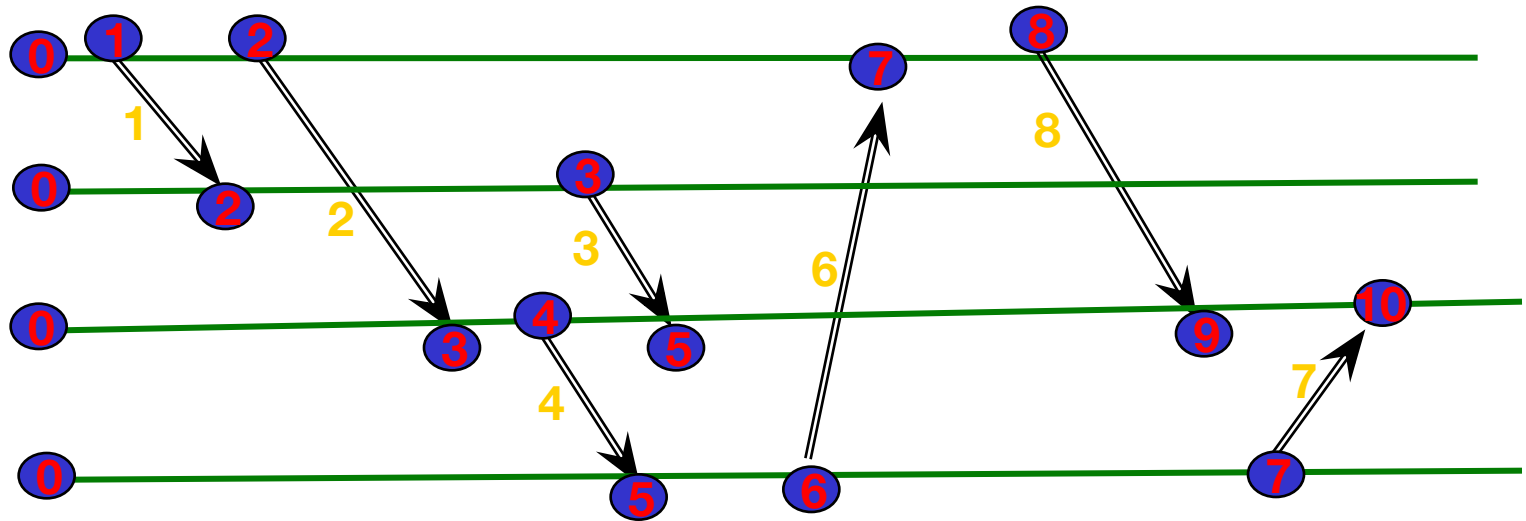
Solution (Lamport): Each process P_i maintains a **local** counter C_i and adjusts it as follows:

- 1) For any two successive events that take place within P_i , the counter c_i is incremented by 1.
- 2) Each time a message m is sent by process P_i , the message is timestamped $ts(m) = c_i$
- 3) Whenever a message m is received by a process P_j , P_j adjusts its local counter c_j to $\max\{C_j, ts(m)\}$; then executes step 1 before passing m to the application.

- Property **P1** is satisfied by (1); Property **P2** by (2) and (3).

Updating Local Clock

Physical Time



Clock Value

timestamp

Message

Attach a timestamp $C(e)$ to each event e , such that:

- **P1:** If a and b are events in the same process, and a happened before in physical time b , then we demand that $C(a) < C(b)$.
- **P2:** If a corresponds to sending a message m , and b to the receipt of that message, then also $C(a) < C(b)$.

Note: C must only increase in each process



Quiz-like question

Notation: ***timestamp(a)*** is the Lamport logical clock associated with event a

By construction if $a \sqsubseteq b \Rightarrow \text{timestamp}(a) < \text{timestamp}(b)$
(if **a happens before b**, then $\text{timestamp}(a) < \text{timestamp}(b)$)

Q: is the converse true?

That is: if $\text{timestamp}(a) < \text{timestamp}(b)$ \Rightarrow  $a \sqsubseteq b$

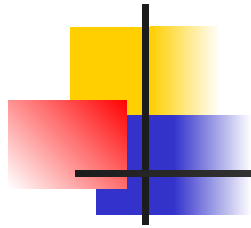
No. If $\text{timestamp}(a) < \text{timestamp}(b)$, it does NOT imply that **a happens before b**

Q: Do I know anything $\text{timestamp}(a) < \text{timestamp}(b)$?

*A: Only that $b \sqsubseteq a$ is FALSE (i.e.. b surely did NOT happen before a, more concrete:
a and b concurrent OR a happened before b)*



Note: Lamport Timestamps: $3 < 7$, but event with timestamp 3 is concurrent to event with timestamp 7, (events are not in 'happen-before' relation).



Last Time: Logical time

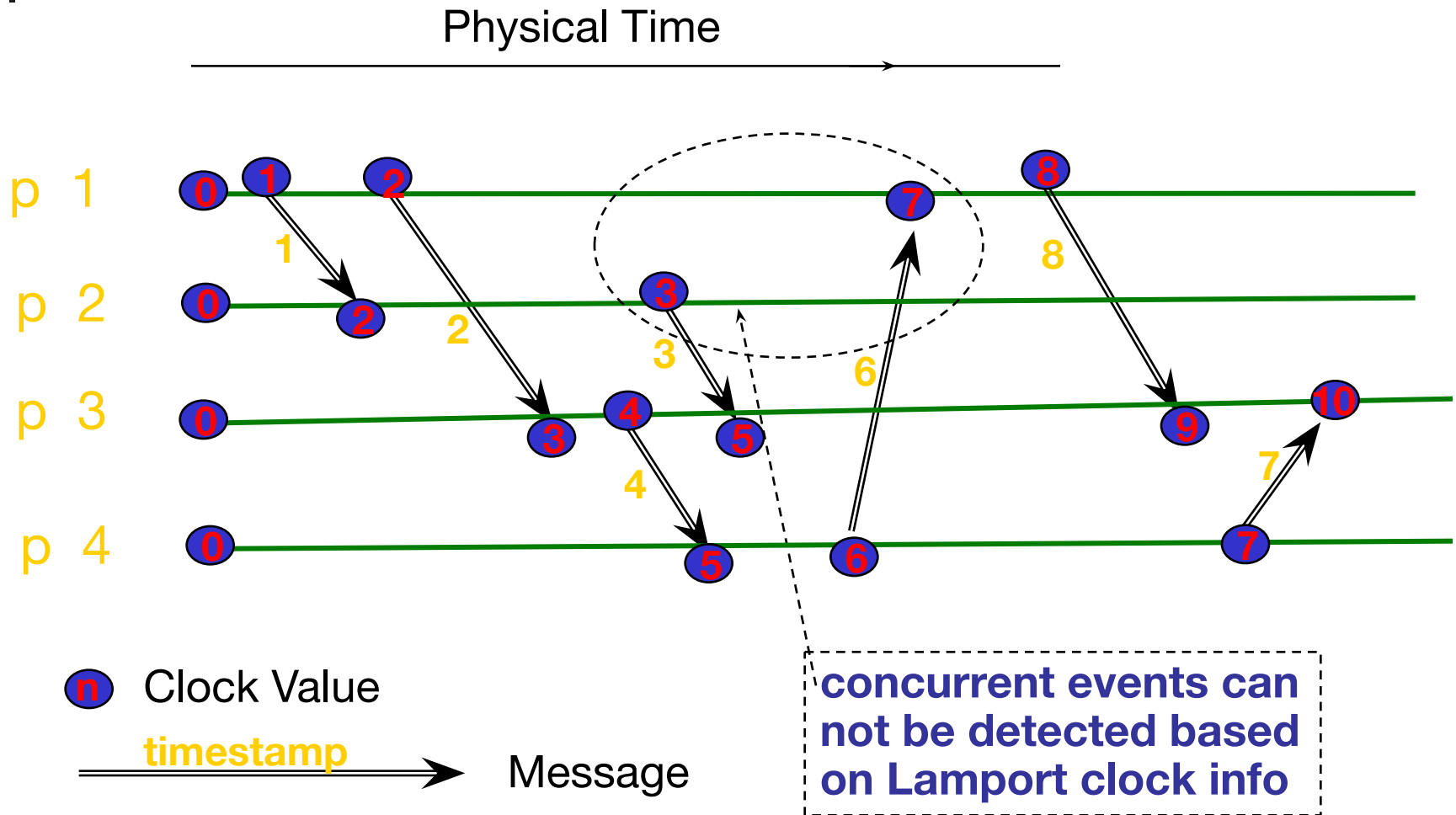
What is that?

- Discrete assignment of sequence numbers to events, which preserves “happens-before” order

How do Lamport clocks work?

- Processes increment their clocks upon receiving/sending new messages and based on other processes' clocks (carried with

Example



Note: Lamport Timestamps: $3 < 7$, but event with timestamp 3 is concurrent to event with timestamp 7, (events are not in 'happen-before' relation).



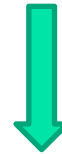
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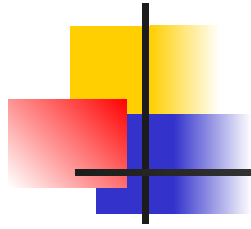
Logical clocks

Assign timestamp to events such that if $a \square b$ then $ts(a) < t(b)$



Build systems

E.g., totally ordered group communication

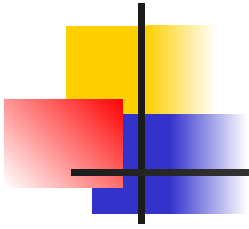


One example use

`\big_detour{start}`

Mutual exclusion

[see separate slide set]



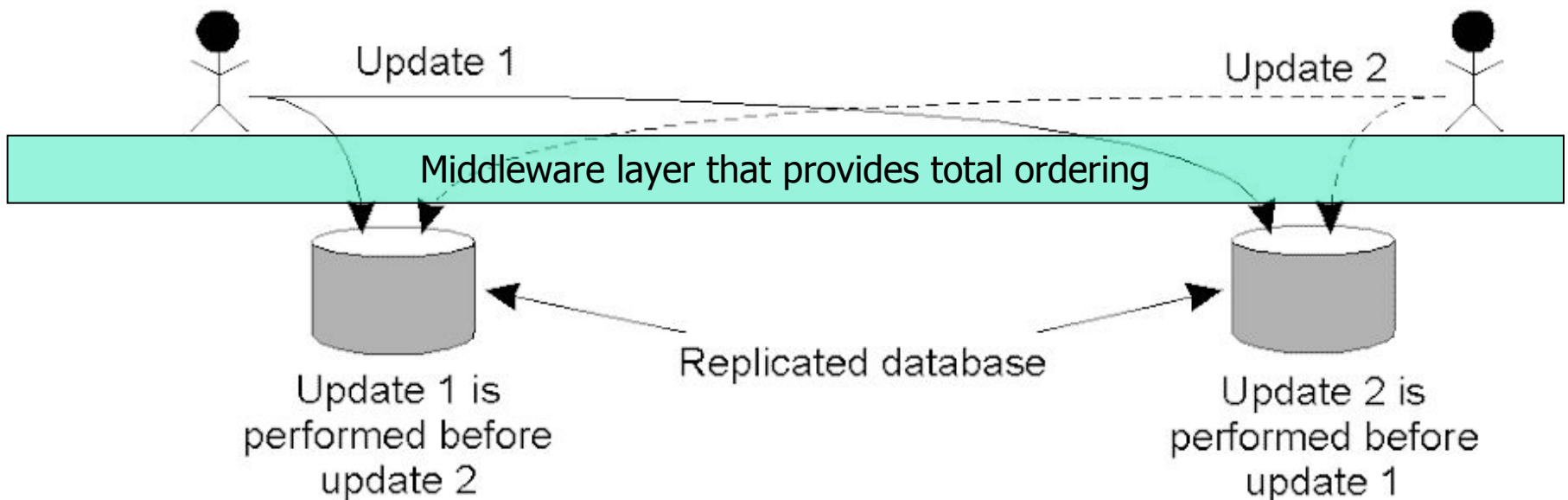
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Example II – replicated state machine

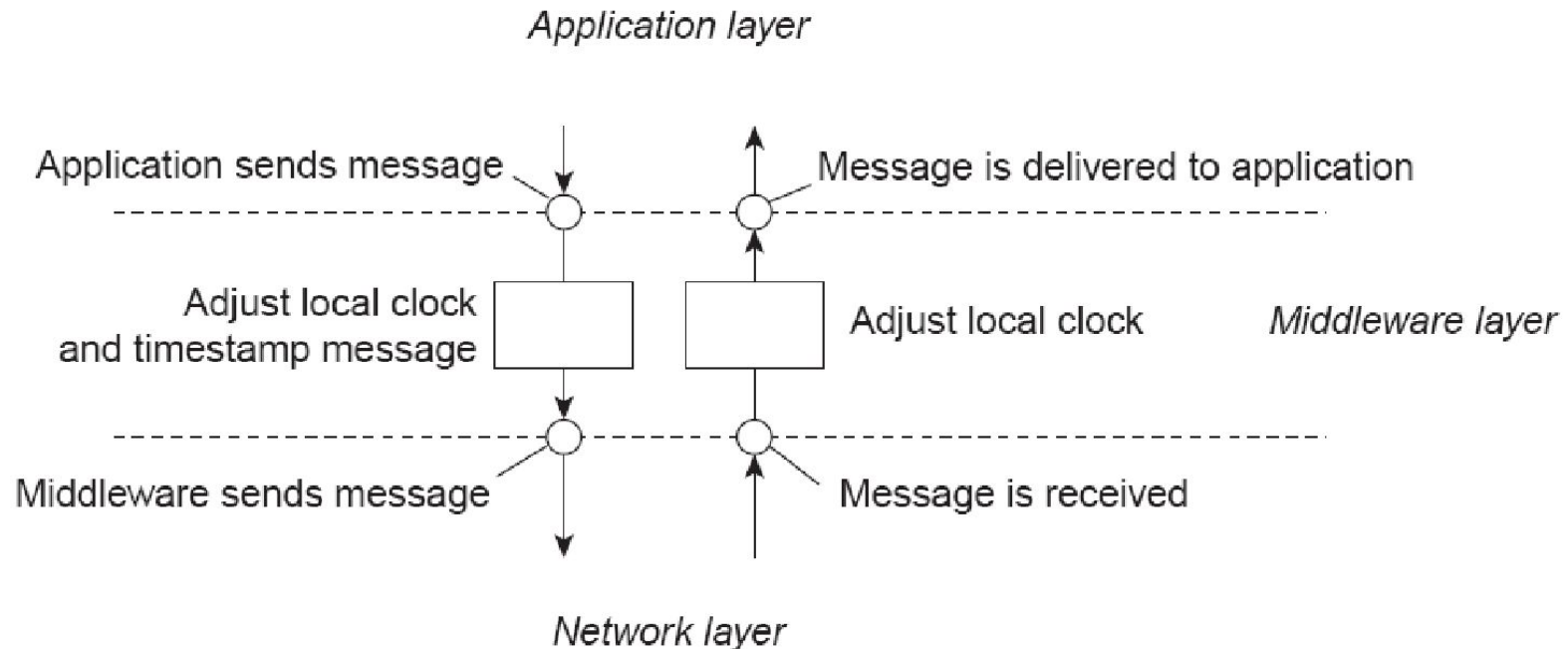
Two accounts:

- Initial state: \$100 account balance
- Update 1: add \$100
- Update 2: add 1% monthly interest

Updates need to be performed in the same order at the two replicas!



Architectural view



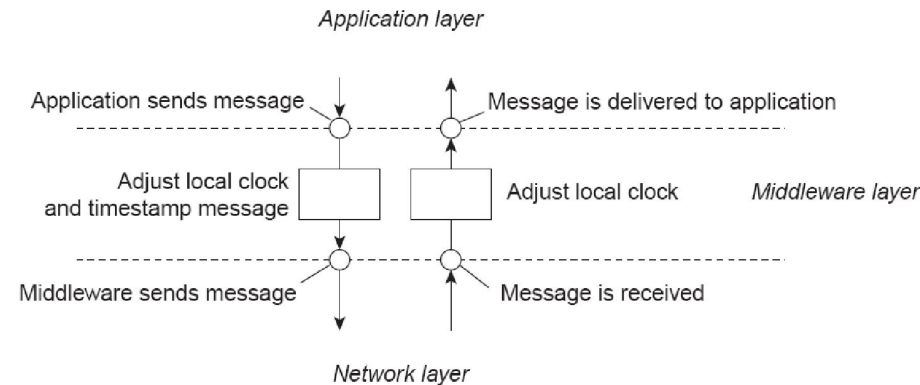
Middleware layer in charge of:

- Local management of logical clocks
 - i.e., stamping messages with (logical) clock times, updating timestamps at message receipt,
- Message ordering: e.g. by delaying delivery/buffering (if needed)

Totally ordered group communication (cont)

Setup (for simplicity)

- All members are both senders and receivers
- A one-to-many communication substrate
- FIFO / Reliable Channels
- No Side Channels



Sketch of a solution:

- Middleware at each member maintains an **ordered queue** of received messages that have not yet been delivered to the application.
- **Main issue:** when to deliver to application such that, at all endpoints, messages are delivered in the same order.
- Each message is timestamped with local logical time then multicasted
 - When multicasted, also message logically sent to the sender itself
- When receiving a message, the middleware layer
 - Adds message to local queue (ordered by sending timestamp)
 - Acknowledges (using multicast) the message
 - Delivers from top of queue to application only when **all** acks for message on top have been received (or optimization: see next slide)



Totally Ordered Multicast – Algorithm

- Process P_i sends timestamped message msg_i to all others. The message itself is put in the local $queue_i$ as well
- Any incoming message msg_j received at P_k is queued in $queue_k$ according to its sent timestamp, and acknowledged to every other process.

Sending /
Receiving

- P_k delivers a message msg_i to its application if:
 - msg_i is at the head of $queue_k$ and
 - for each process $P_{x'}$ there is an ack or a message in $queue_k$ with a larger sending timestamp.

Deliver to
application

Guarantee: all messages are delivered in the same order at all destinations

Note: We assume that communication is **reliable** and **FIFO ordered**.



Quiz-Like Questions

- What's the complexity of the protocol in terms of number of messages
- What happens if we drop channel reliability assumption?
 - Does the protocol still work? If it fails, explain how.
- What happens if we drop channel FIFO assumption?
 - Does the protocol still work?
 - How would you change the previous protocol to still work correctly without this assumption?
- Assume you have a bound on message propagation time in the network. Design a protocol that provides total ordering (and generates less traffic)



Define (partial) order for events

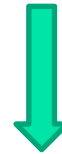
"happens before" relation



Logical clocks

Assign timestamp to events
such that:

if $a \sqsubseteq b$ then $ts(a) < ts(b)$



ISSUE

By design (with Lamport timestamps)
 $a \sqsubseteq b \Rightarrow timestamp(a) < timestamp(b)$

But

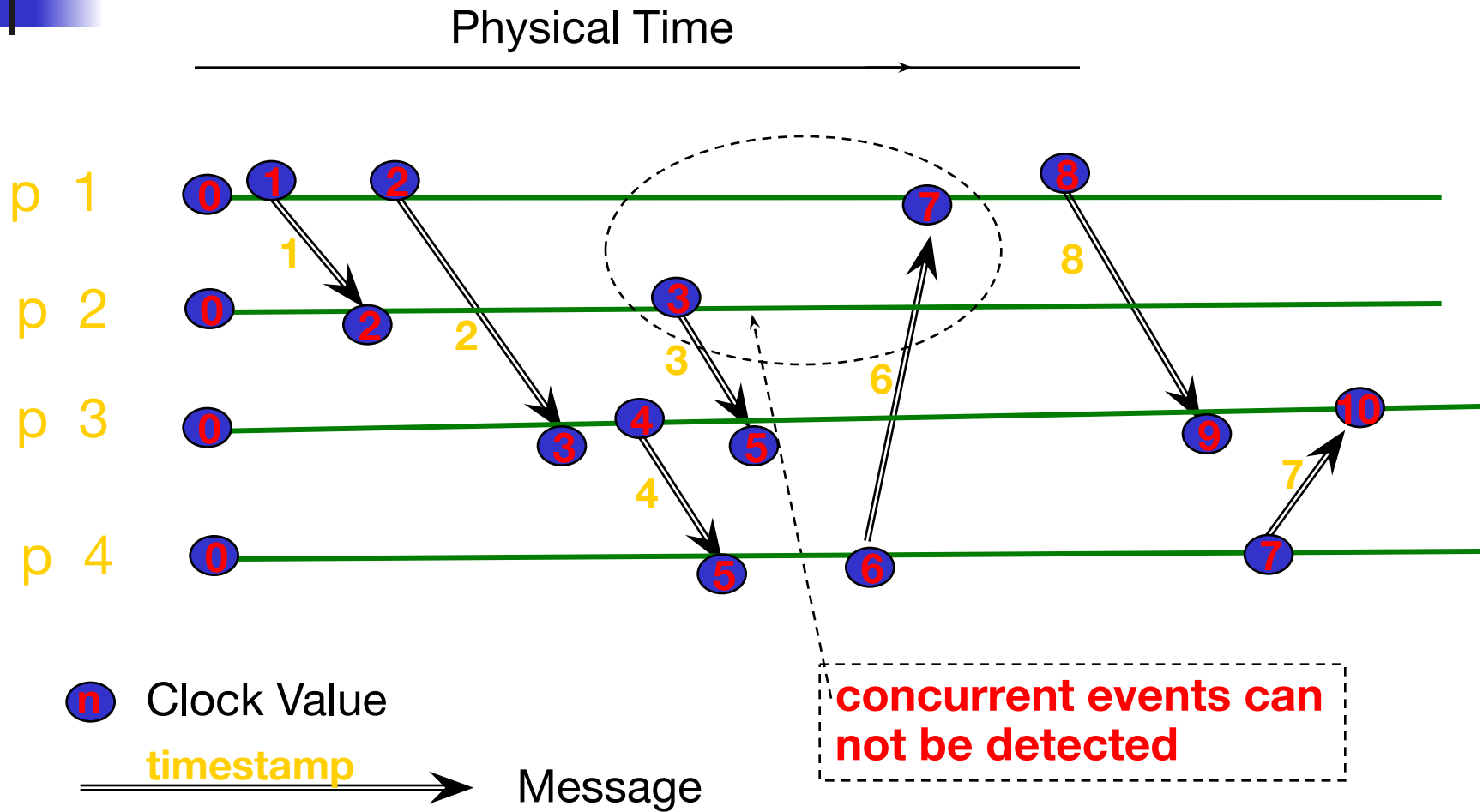
If $timestamp(a) < timestamp(b)$ one can not
reason about relative ordering of a and b

[the only thing you know is that $b \sqsubseteq a$ is FALSE]

Build systems

E.g., totally ordered
group communication

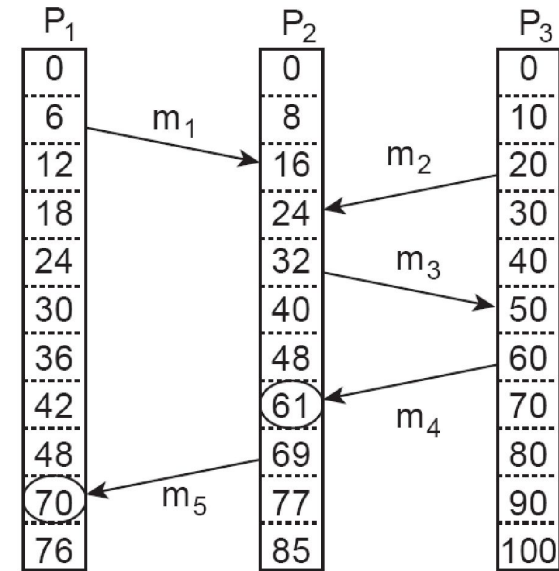
Example



Issue: Lamport Timestamps $3 < 7$, but event with timestamp 3 is concurrent to event with timestamp 7, i.e., events are not in 'happen-before' relation.

Causality

- Issue: Lamport timestamps don't properly capture **causality**
 - Introduce **more ordering than necessary**
- Applications often need to reason about (i.e., order similarly) **only** causally related messages.
 - Example: news postings have multiple independent threads of messages.
 - What are the constraints on ordering?
- To model causality – **vector** timestamps
 - **Intuition**: each item in vector logical clock for one causality thread.





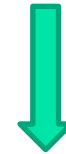
Define partial order for events

"happens before"
relationship



Vector clocks

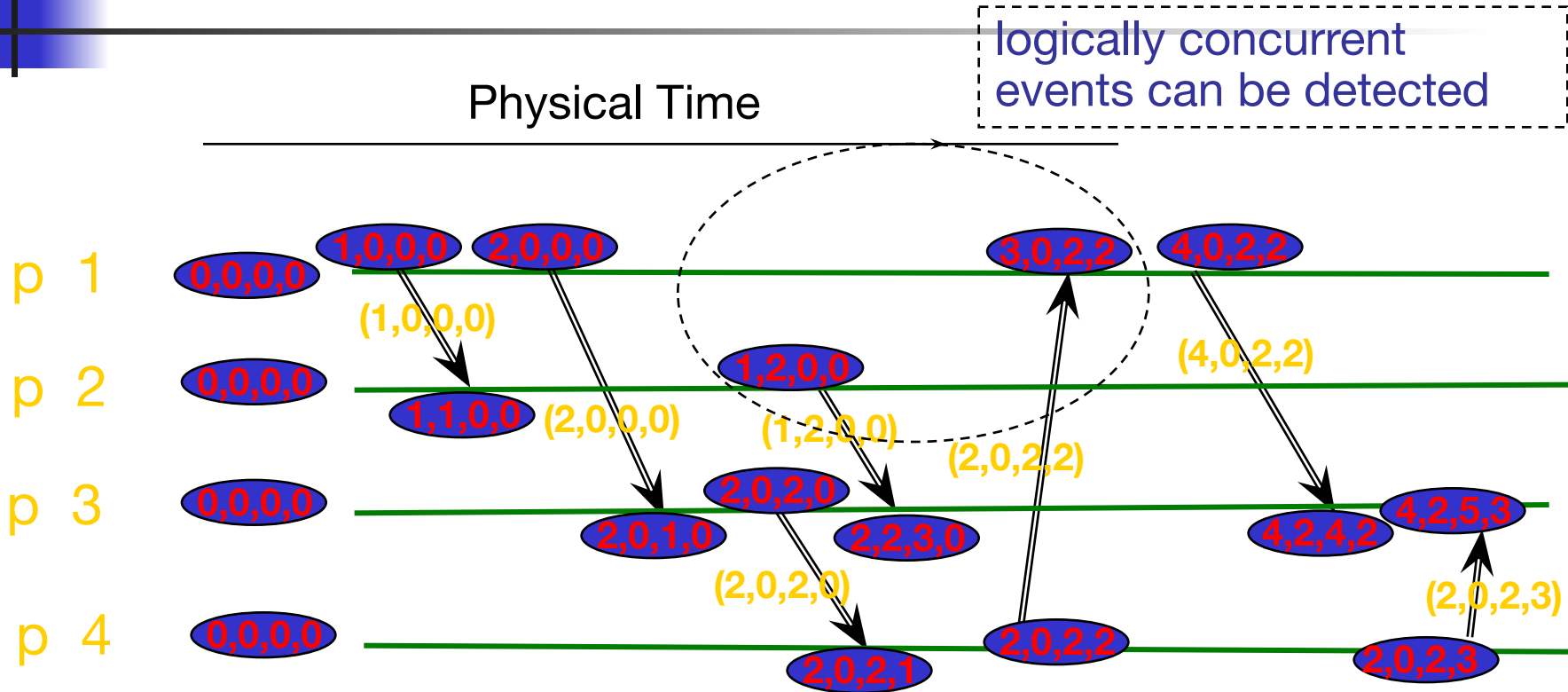
Assign timestamps to
keep track of event
causality



Build systems

E.g., **causally** ordered
group communication

Example: Vector Timestamps



(n,m,p,q) Vector logical clock
(vector timestamp)

Message

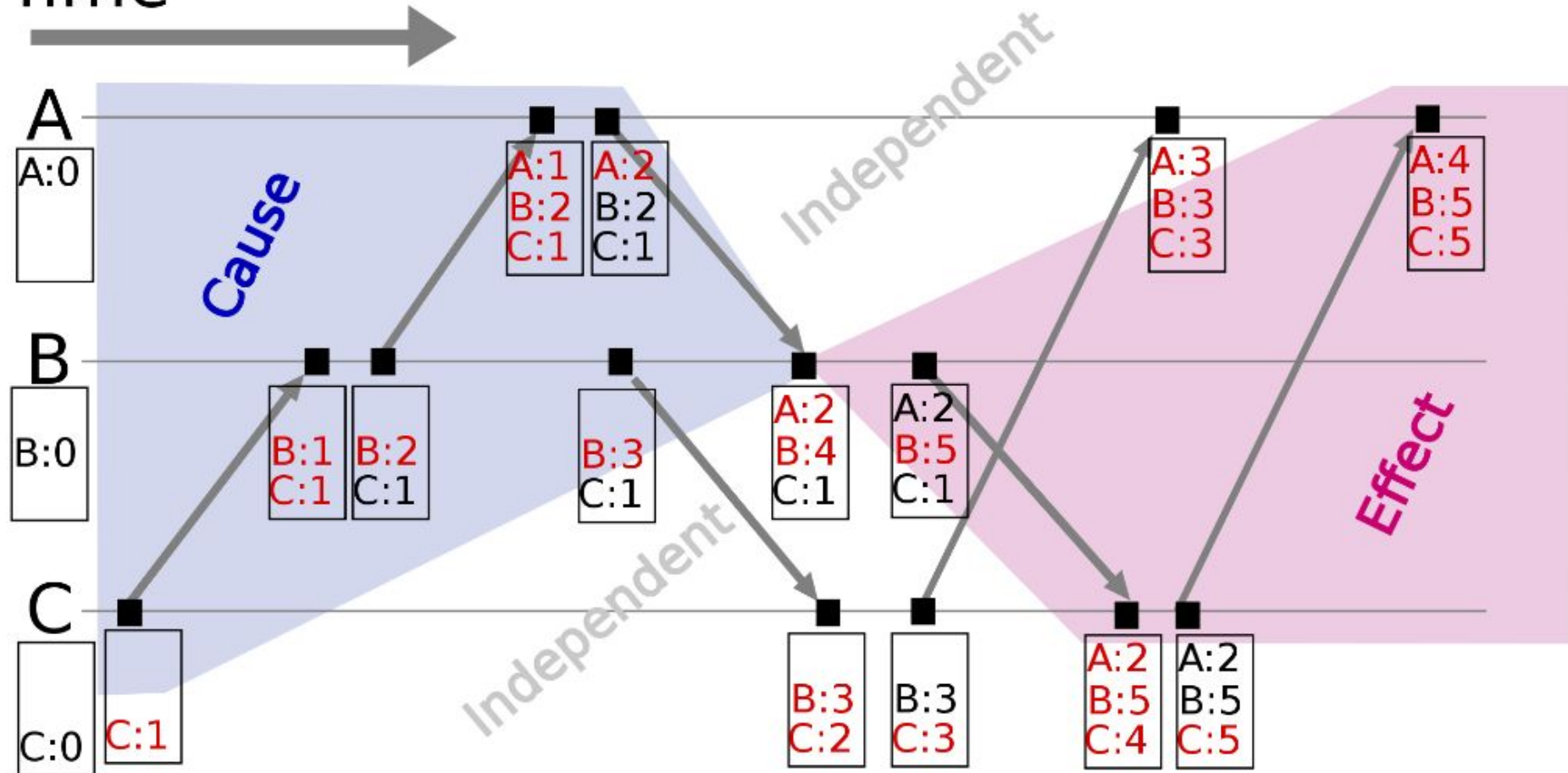
Notation

♦ $VT_1 < VT_2$,
iff for all j ($1 \leq j \leq n$) such that $VT_1[j] \leq VT_2[j]$
and
exists j ($1 \leq j \leq n$) such that $VT_1[j] < VT_2[j]$

♦ VT_1 is **concurrent** with VT_2
iff (not $VT_1 < VT_2$ AND not $VT_2 < VT_1$)

Vector clocks/timestamps enable reasoning about causality

Time



Events in the blue region are the causes leading to event B4, whereas those in the red region are the effects of event B4



Vector clocks: the formal definition

- Each process P_i has an array $VC_i[1..n]$ of clocks (all initially at 0)
 - $VC_i[j]$ denotes the number of events that process P_i knows have taken place at process P_j
- P_i increments $VC_i[i]$: when an event occurs
 - local event, message sending, message receiving
 - timestamp of the event is vector value
- When **sending**
 - Messages sent by P_i includes a **vector timestamp** $vt(m)$.
 - Result: upon arrival, recipient knows P_i 's timestamp.
- When P_j **receives** a msg from P_i with vector timestamp $ts(m)$:
 - for $k \neq j$: update each $VC_j[k]$ to $\max\{VC_j[k], ts(m)[k]\}$

Note: vector timestamps require a static notion of system membership



Comparing vector timestamps

Notation

- ❖ $VT_1 < VT_2$,
iff for all j ($1 \leq j \leq n$) such that $VT_1[j] \leq VT_2[j]$
and
exists j ($1 \leq j \leq n$) such that $VT_1[j] < VT_2[j]$
- ❖ VT_1 is **concurrent** with VT_2
iff (not $VT_1 < VT_2$ AND not $VT_2 < VT_1$)



Quiz like problem

Show that:

$a \sqsubseteq b$ if and only if $\mathbf{vectorTS}(a) < \mathbf{vectorTS}(b)$

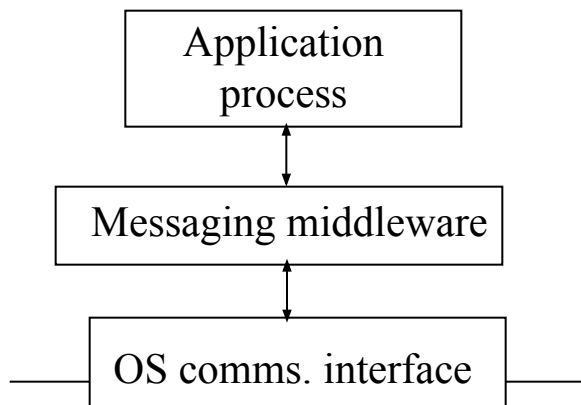


Extending group communication

ASSUMPTIONS

- messages are multicast to (named) process groups
- reliable and FIFO channels
- processes don't crash
- processes behave as specified (i.e., we are not considering Byzantine behaviour)

Architectural view



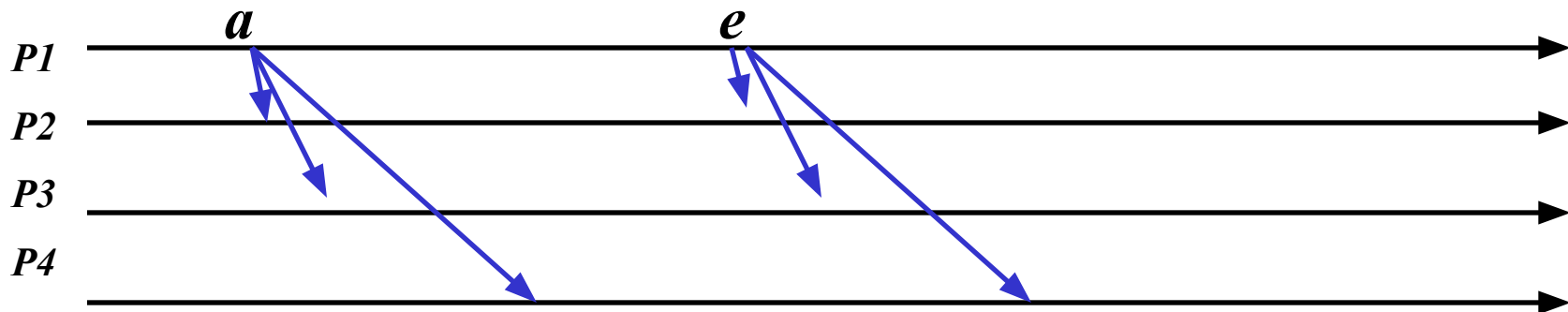
*Application: chooses delivery order of message service
e.g. **total order, FIFO order, causal order**
(last time we looked at 'total order')*

*Middleware: may reorder/delay message delivery
to application by buffering messages to implement
reordering policy*

*Basic network layer: provides reliable FIFO from
each source (done at lower levels)*

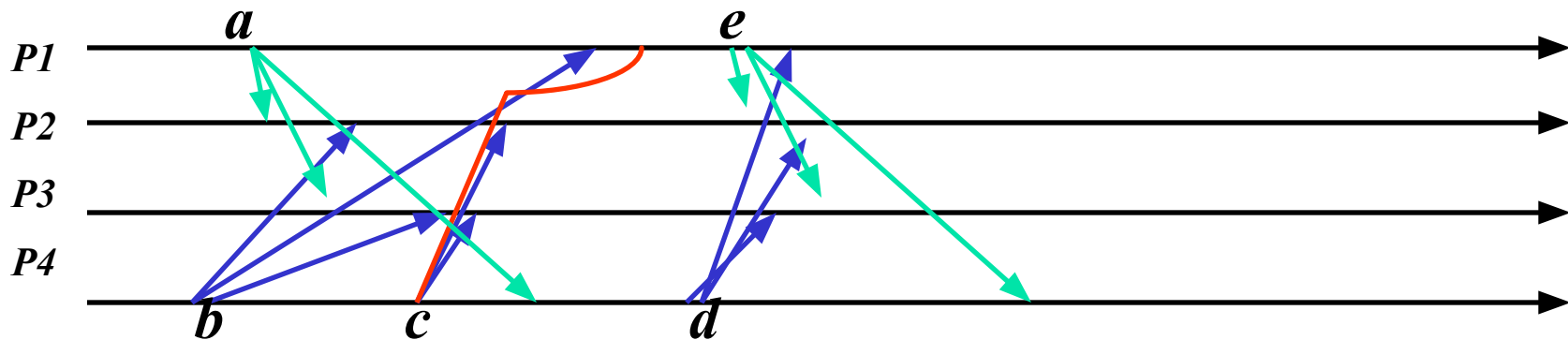
FIFO multicast

- *FIFO (or sender ordered) multicast: Messages sent by any single sender are received in the same order*
 - Nothing guaranteed for relative ordering of messages sent by two different senders



FIFO multicast

- *FIFO (or sender ordered) multicast: Messages sent by any single sender are received in the same order*
 - Nothing guaranteed for relative ordering of messages sent by two different senders



- *delivery of *c* to *P1* is delayed until after *b* is delivered*
- **d* and *e* are received in different order at *P2* and *P3**

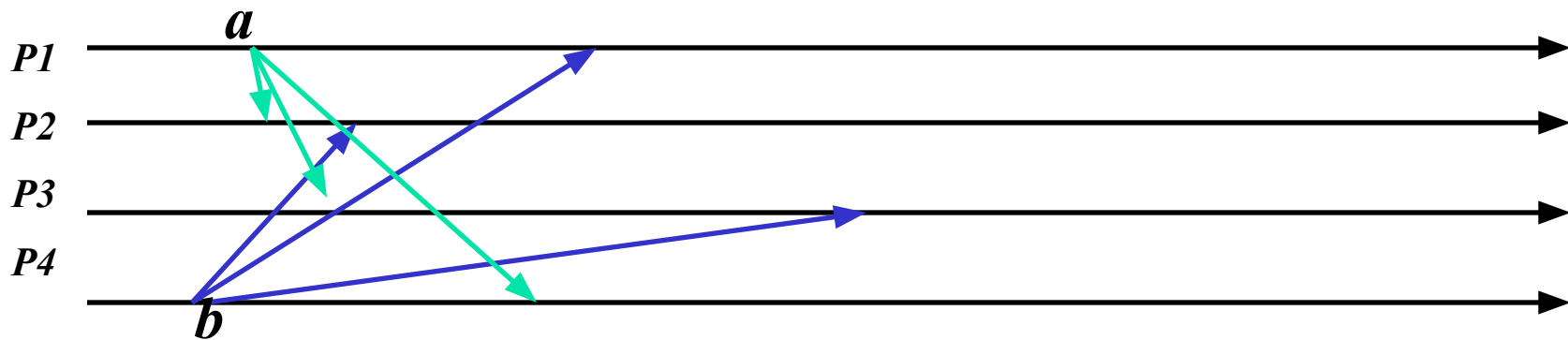


Implementing FIFO multicast

- Basic reliable (i.e., no message loss) multicast has this property
 - Without failures all we need is to run it on FIFO channels (like TCP)
 - [Later: dealing with node failures]

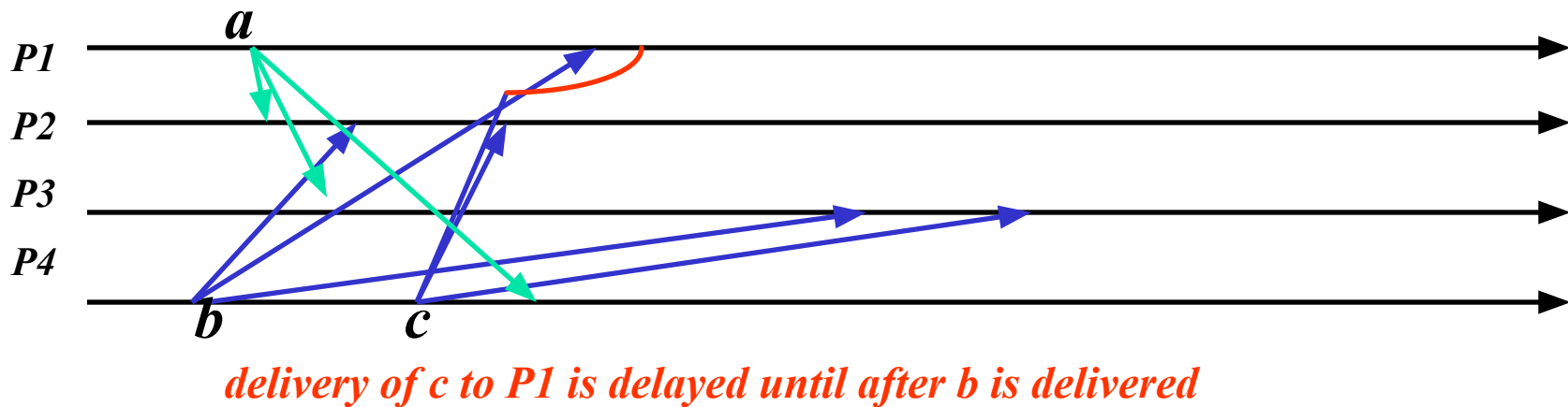
Causal multicast

- *Causal (or happens-before) ordering*
- *If $\text{send}(a) \rightarrow \text{send}(b)$ (i.e., there was some causal relationship)
 - *then $\text{deliver}(a)$ occurs before $\text{deliver}(b)$ at common destinations**



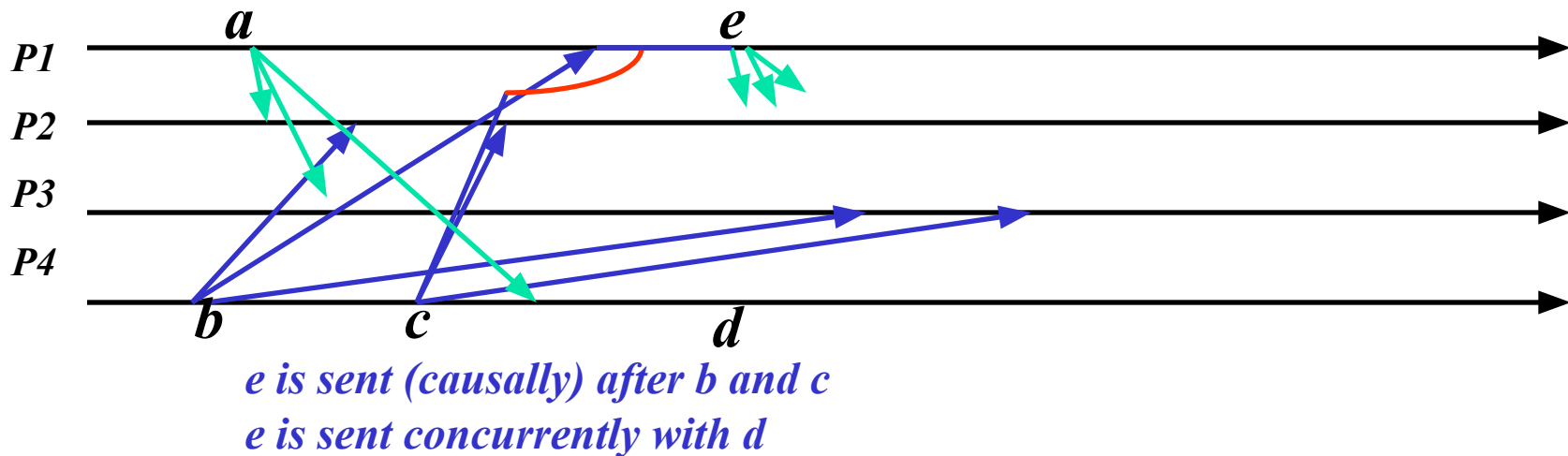
Ordering properties: Causal

- *Causal (or happens-before) ordering*
- *If $\text{send}(a) \rightarrow \text{send}(b)$ (i.e., there was some causal relationship)*
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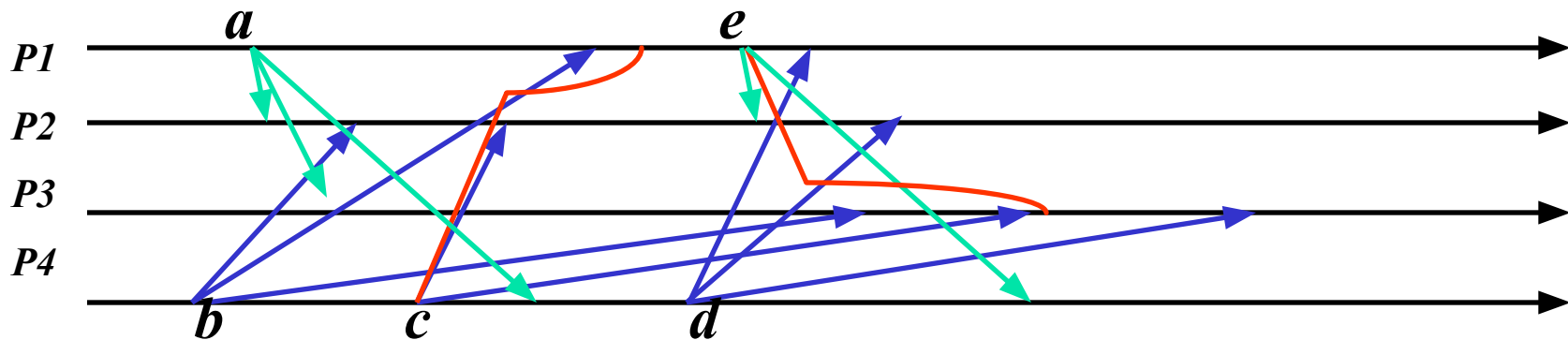
Ordering properties: Causal

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Ordering properties: Causal

- *Causal (or happens-before) ordering*
- *If $\text{send}(a) \rightarrow \text{send}(b)$*
(i.e., if there was some causal relationship between a and b)
 - *then $\text{deliver}(a)$ occurs before $\text{deliver}(b)$ at common destinations*



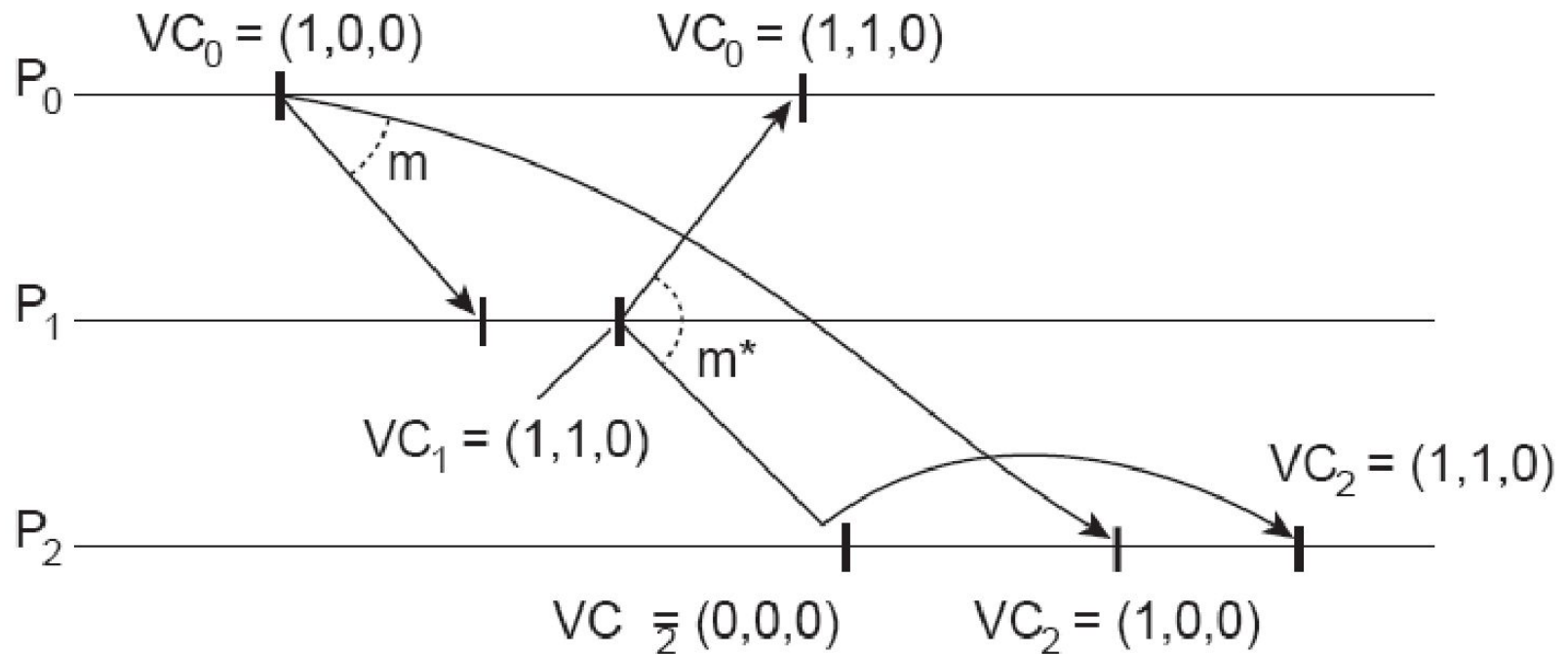
delivery of c to P1 is delayed until after b is delivered

delivery of e to P3 is delayed until after b&c are delivered

delivery of e and d to P2 and P3 in any relative order (concurrent)

Implementing causally ordered multicast

[note slightly different update rule for vector clocks to enable counting the number of messages sent by each machine]

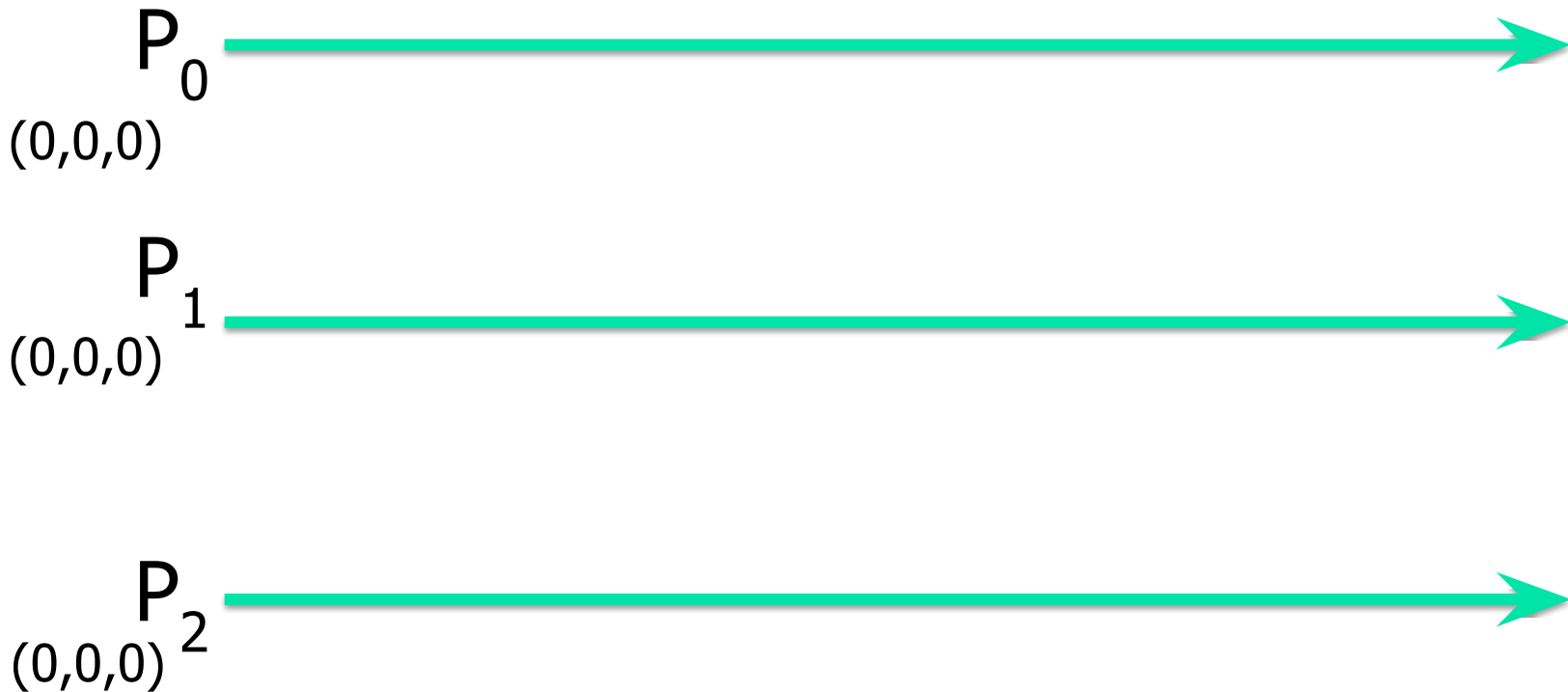


Now suppose that P_j receives a message m from P_i with (vector) timestamp $ts(m)$. The delivery of the message to the application layer will then be delayed until the following two conditions are met:

1. $ts(m)[i] = VC_j[i] + 1$
2. $ts(m)[k] \leq VC_j[k]$ for all $k \neq i$



Implementing causally ordered multicast

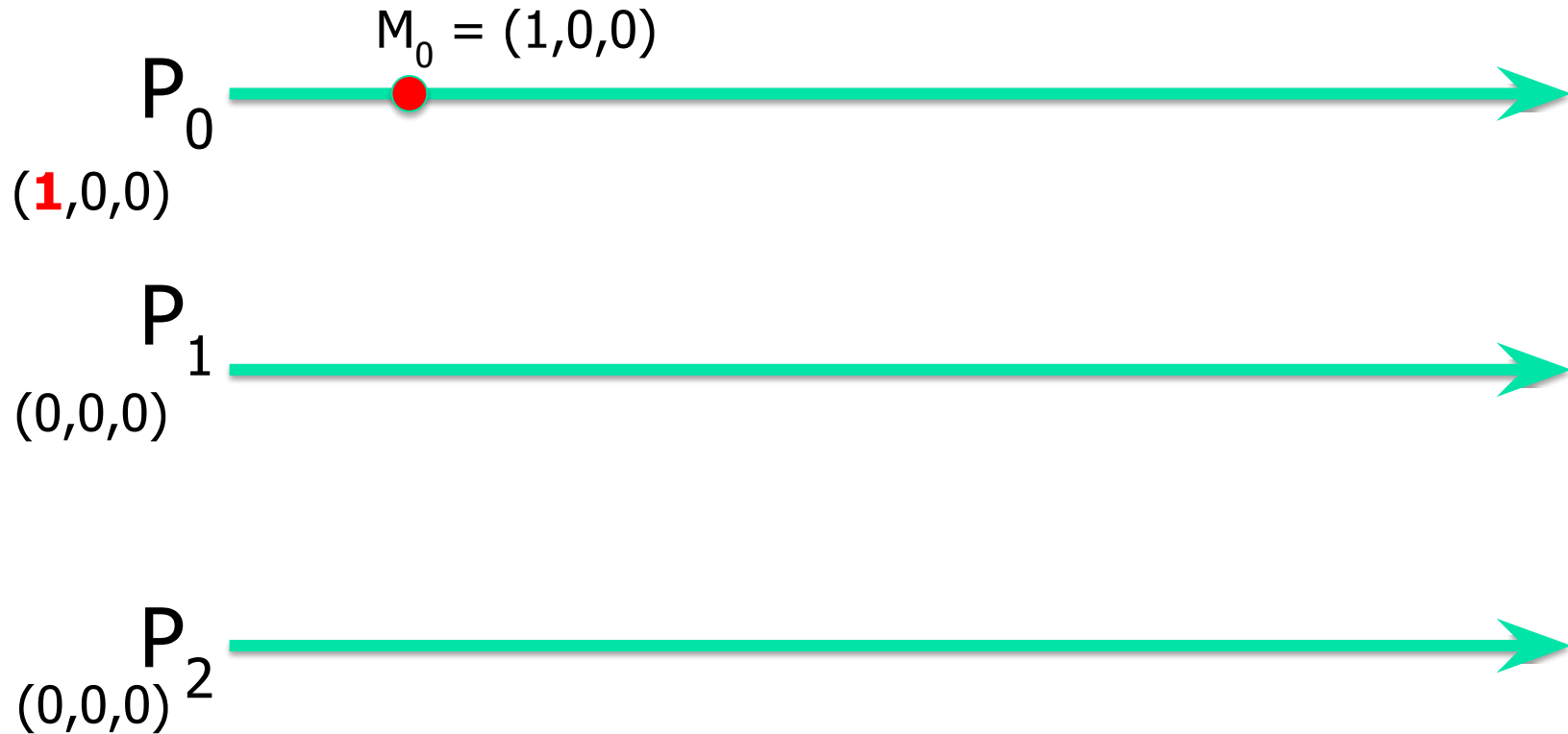


Vector clocks on each process all initialized at $(0,0,0)$

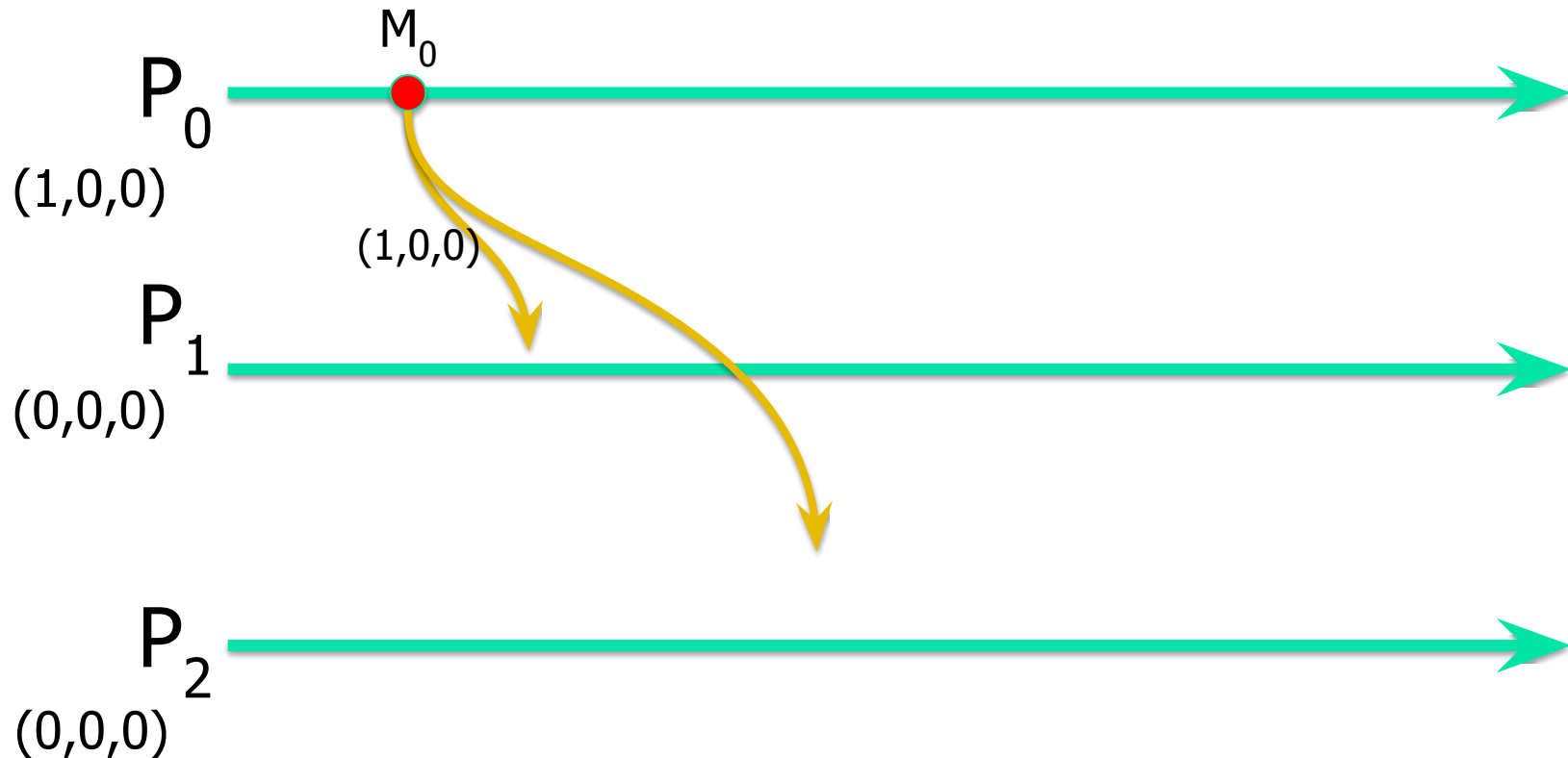
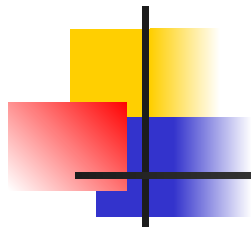
At process P_i position i will count how many messages P_i has sent

position $k \neq i$ will count how many messages P_i has received from P_k

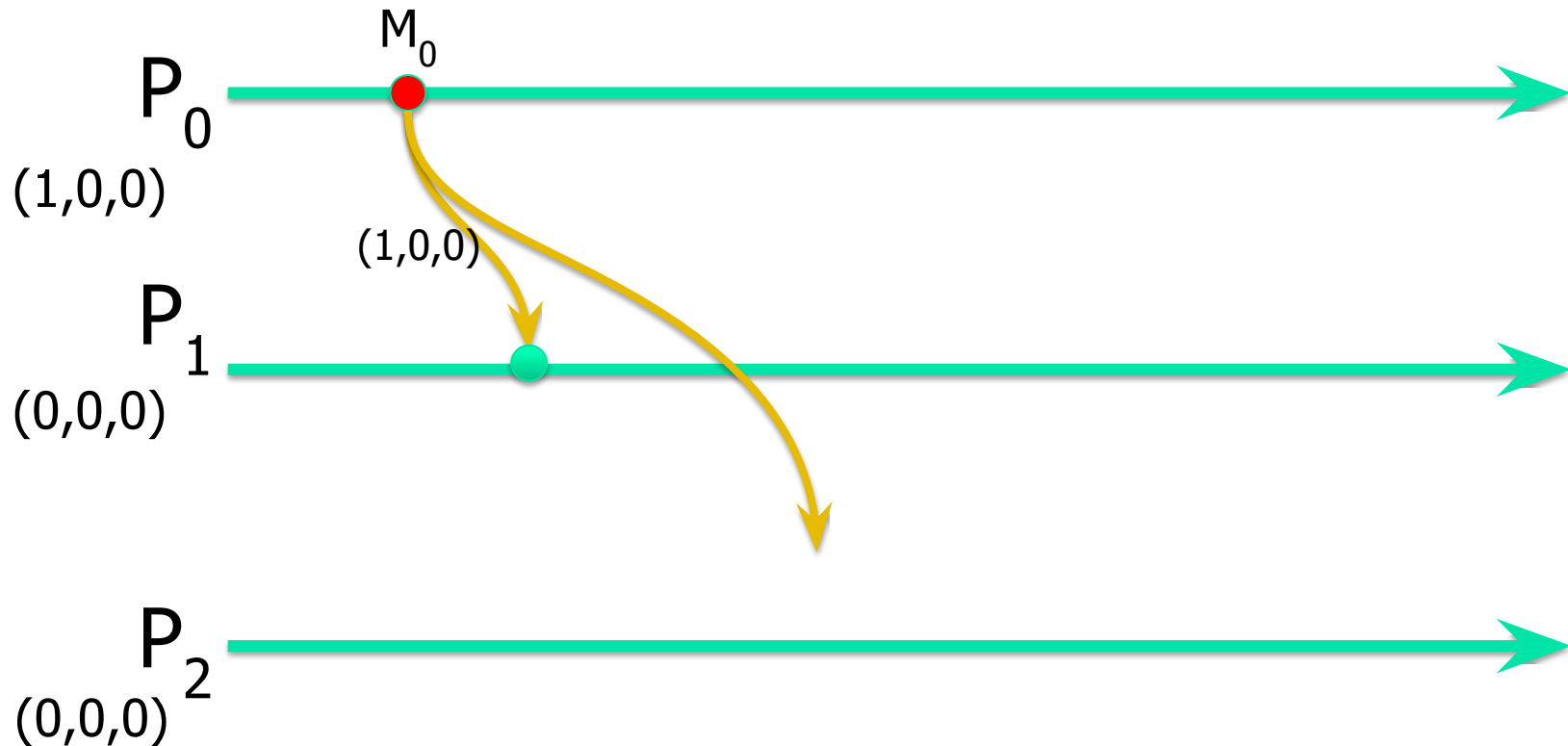
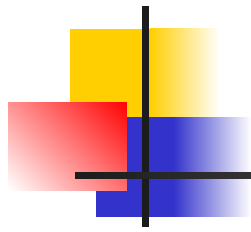
[note slightly different update rule for vector clocks to enable counting the number of messages sent by each machine]



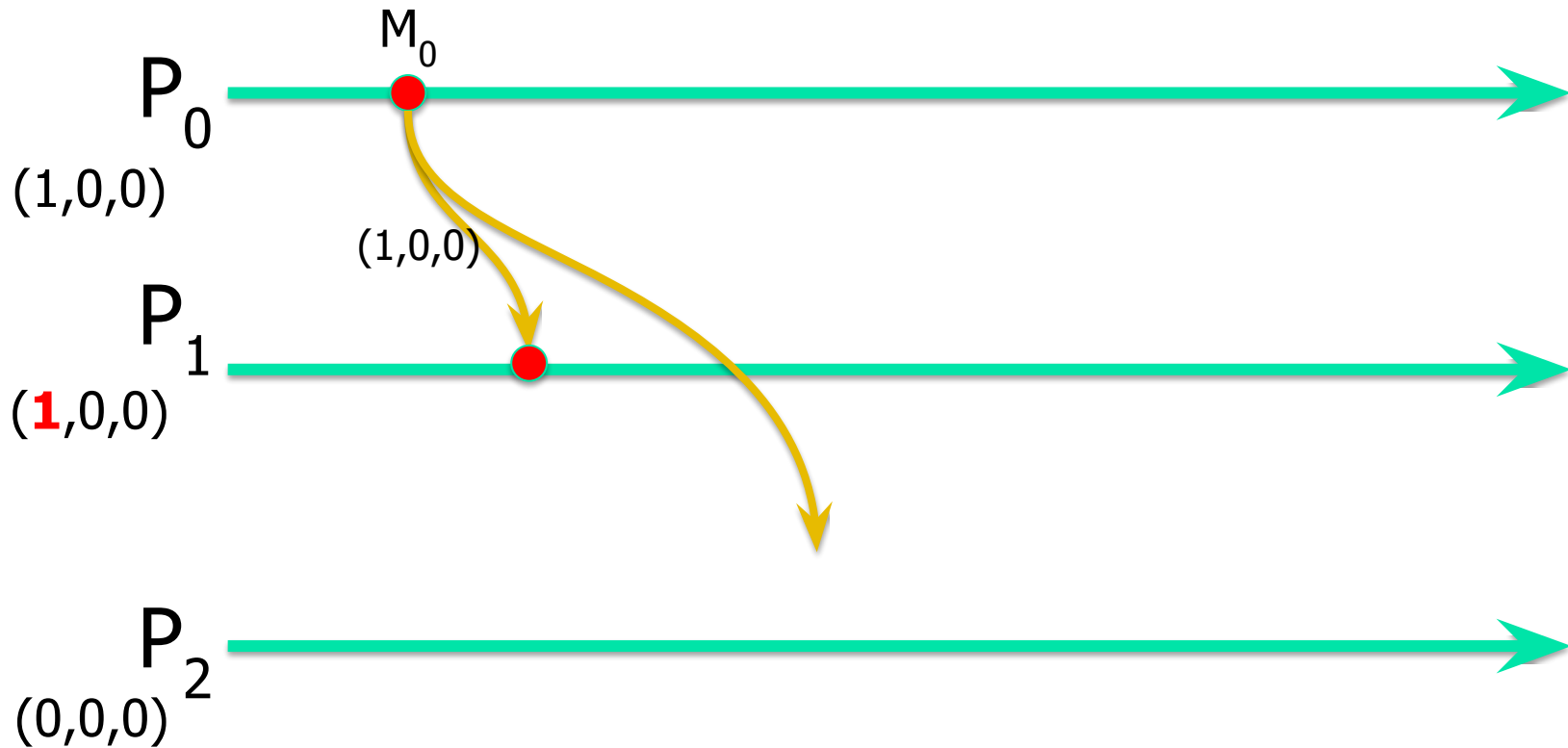
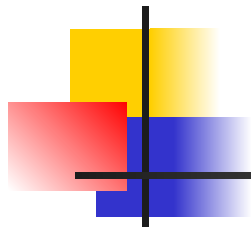
- Message M_0 is initiated at P_0 and can be delivered to application locally.
- Vector clock at P_0 is updated.
- M_0 is sent with its vector clock



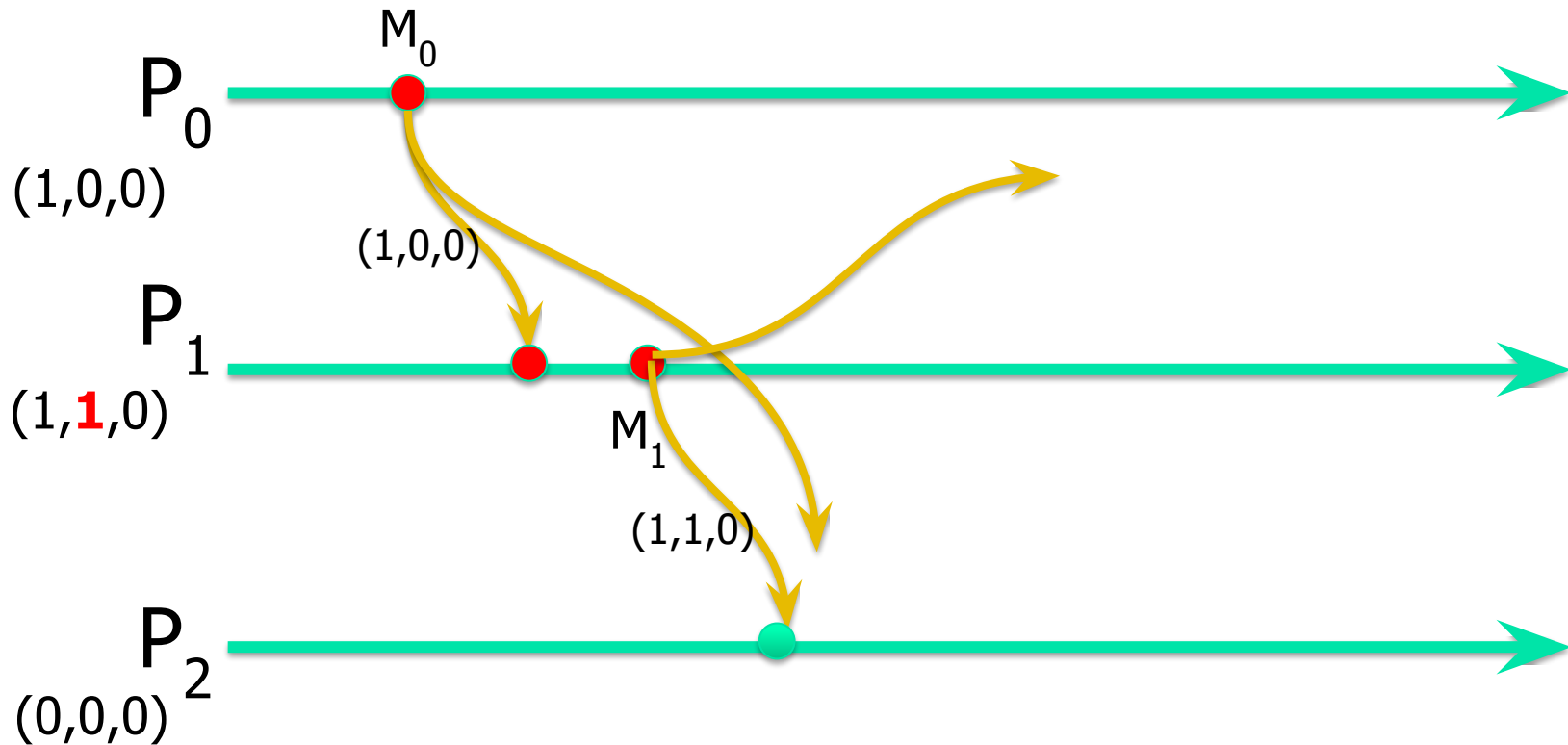
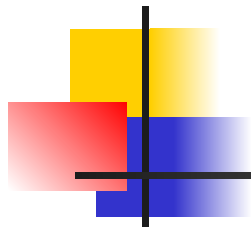
- Message M_0 is initiated at P_0 and can be delivered to the application locally.
- Vector clock at P_0 is updated.
- M_0 is sent with its vector clock to the other processes



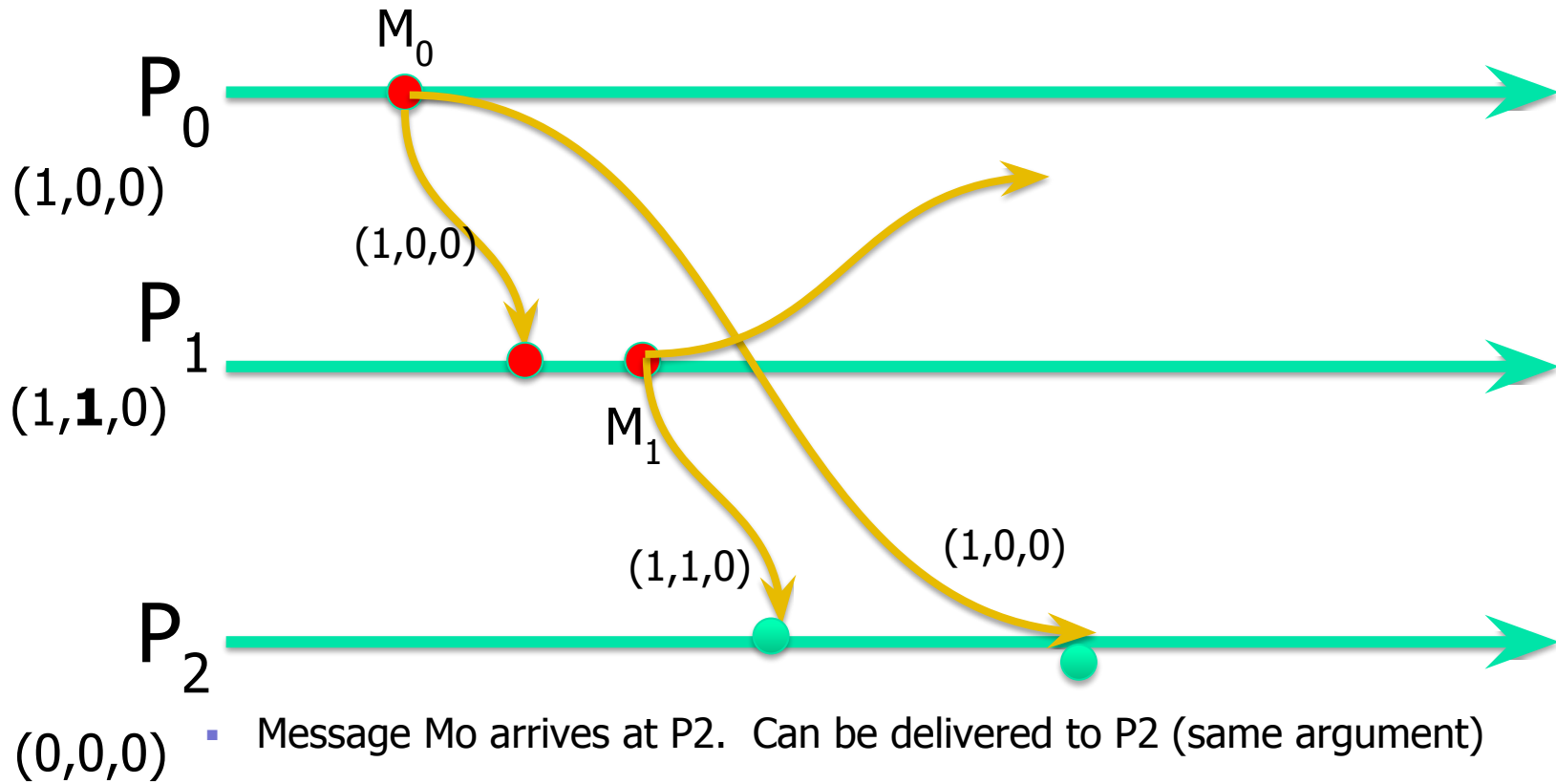
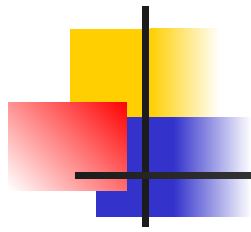
- Message M_0 arrives at P_1
- Message M_0 can be delivered to the application at P_1 : the check - all messages that have potentially been received at P_0 before generating M_0 have been seen by P_1 as well

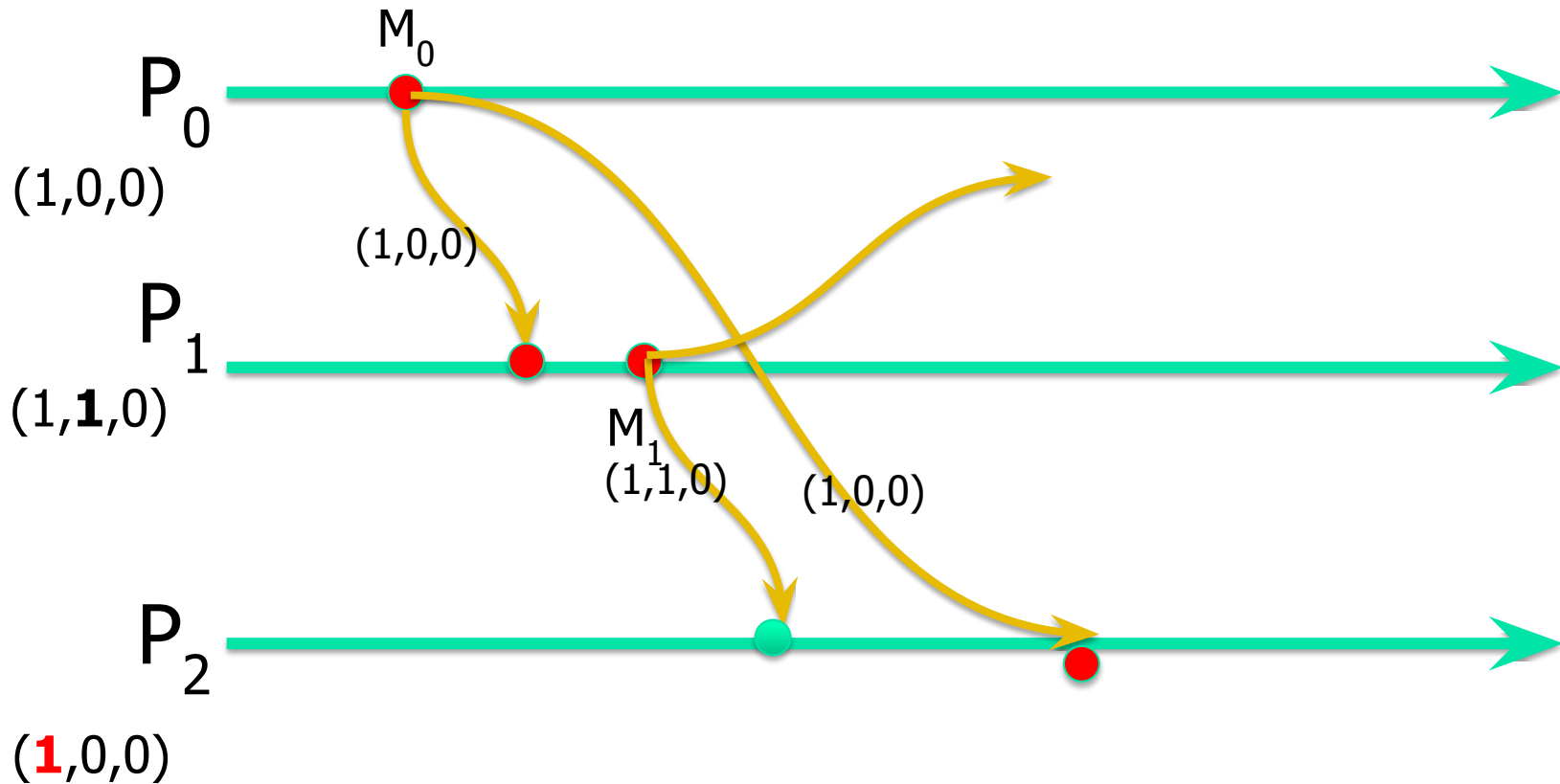
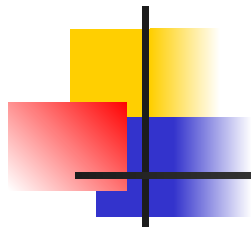


- Message M_0 is delivered at P_1
- P_1 updates its vector clock

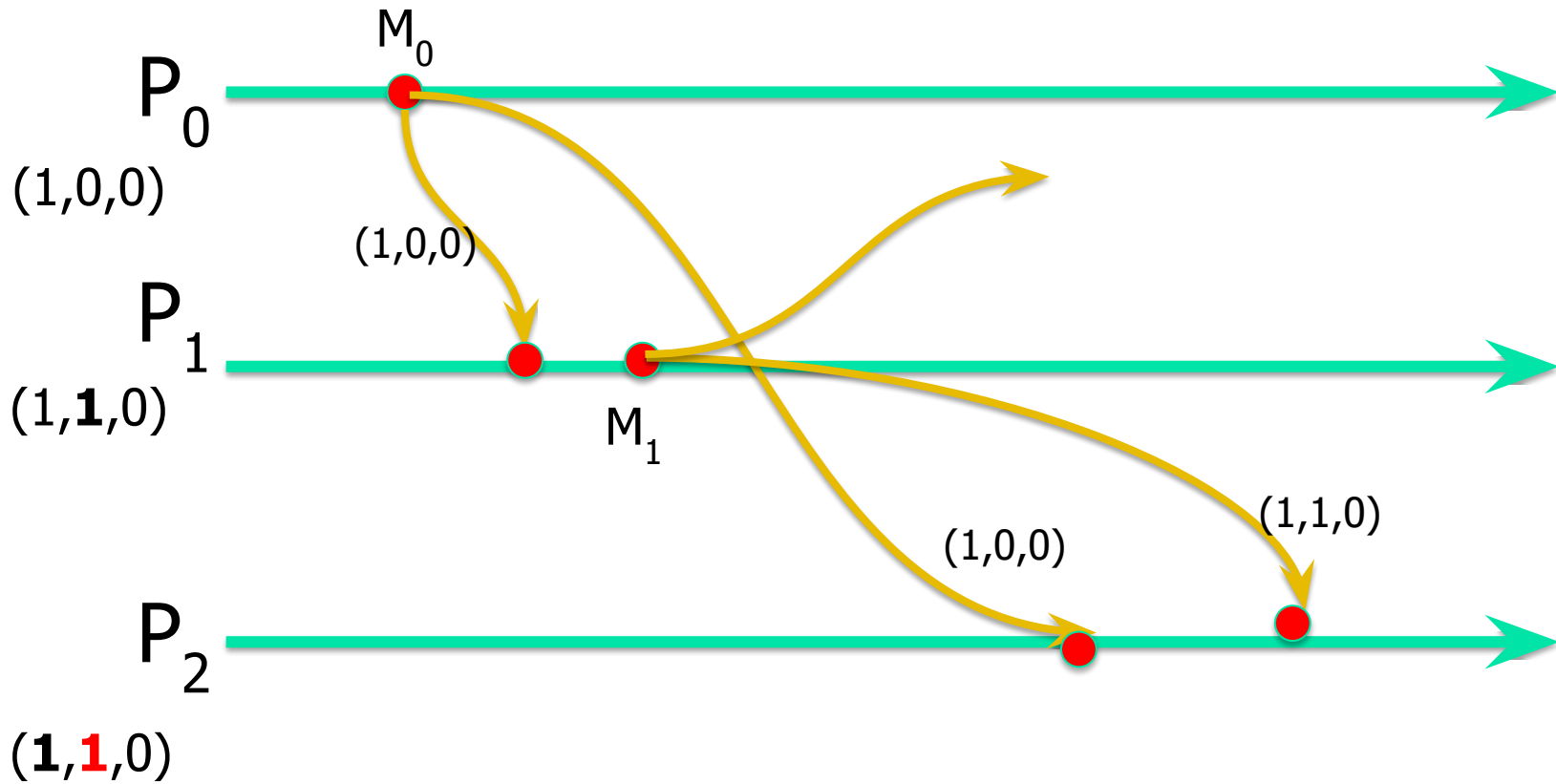
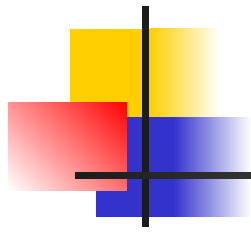


- Message M_1 is created by P_1 . The message can be delivered to local application at P_1 . P_1 updates its vector clock. This timestamp $(1,1,0)$ is carried by M_1 .
- Message M_1 arrives at P_2 . Can not be delivered to P_2 since, M_1 's vector clock at position 0 implies that, when M_1 was created it has one message from P_0 and P_2 has not yet seen that message.

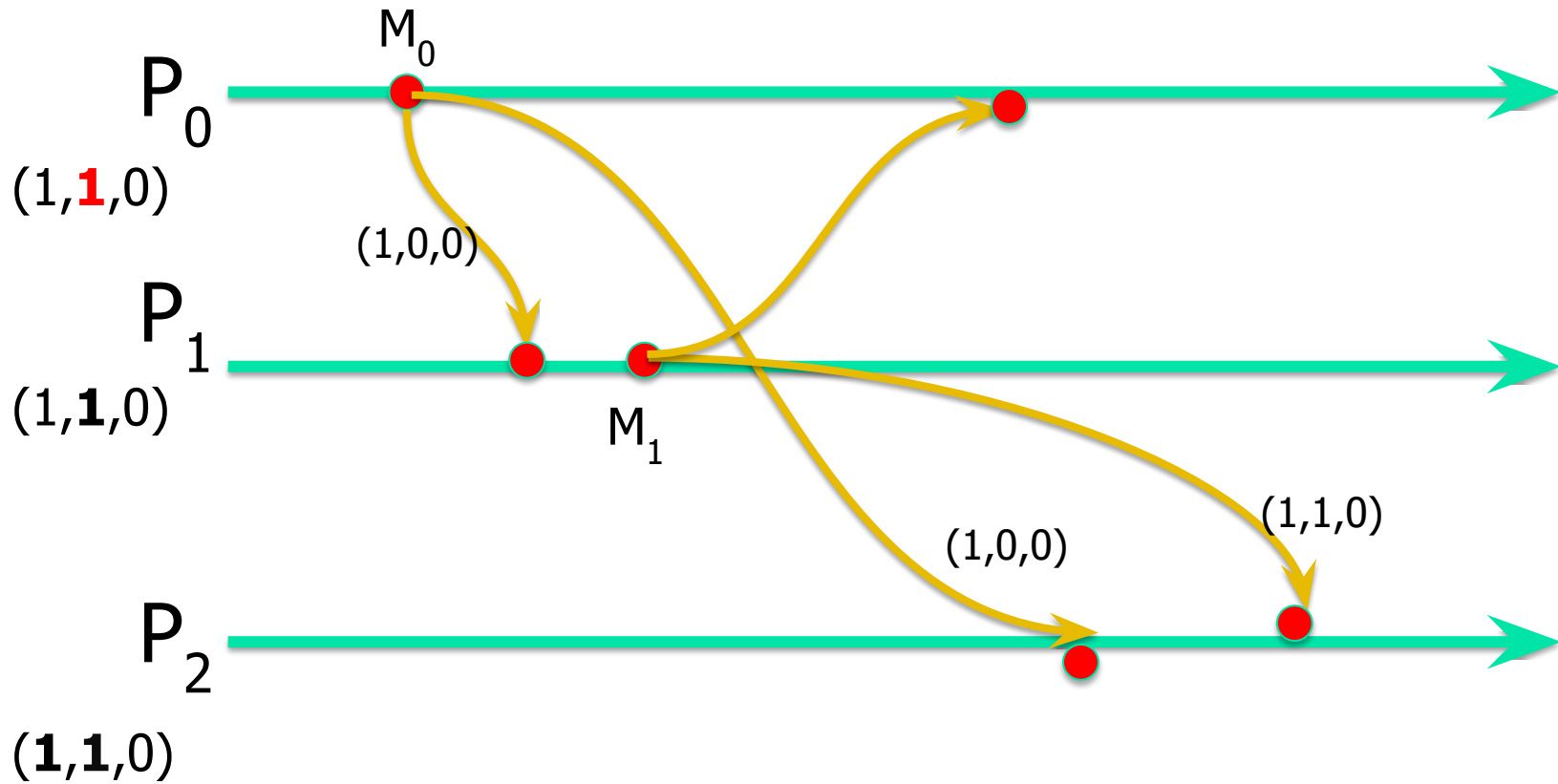
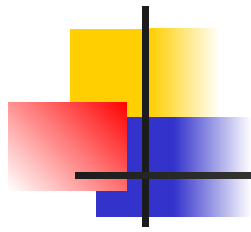




- Message M_0 is delivered to P_2 . P_2 's vector clock is updated.
- Now P_2 can look at the other messages it has in its queue



- Now M_0 can be delivered to application at P_2 . P_2 's vector clock is updated.



- M_1 arrives at P_0 and can be delivered to application. P_0 updates its vector clock



Implementing causal order multicast

- Start with FIFO multicast
- Strengthen this into a causal multicast by adding vector time
- **Advantages** (compared with totally ordered multicast)
 - No additional messages needed!
 - Lower overhead
 - causal multicast (as well as FIFO multicast) are *asynchronous*:
 - Sender doesn't get blocked and can deliver a copy to itself without "stopping" to learn a safe delivery order



Sample quiz question

6.11 Five processes 0, 1, 2, 3, 4 in a completely connected network decide to maintain a *distributed bulletin board*. No central version of it physically exists, but every process maintains an image of it. To post a new bulletin, each process multicasts every message to the other four processes, and recipient processes willing to respond to an incoming message multicast their responses in a similar manner. To make any sense from a response, every process must *accept* every message and response in *causal order*, so a process receiving a message will postpone its *acceptance* unless it is confident that no other message causally ordered before this one will arrive in future.

To detect causality, the implementation uses *vector clocks*. Each message or response is tagged with an appropriate vector time stamp. Figure out (a) a rule for assigning these vector time stamps and (b) the corresponding algorithm using which a process will decide whether to accept a message immediately or postpone its acceptance.



So far ...

- Physical clocks
 - Two applications
 - Provide at-most-once semantics
 - Global Positioning Systems
- 'Logical clocks'
 - Where only ordering of events matters
- Next:
 - Replication
 - One application that puts everything together