

Scalable Distributed Topologies

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Graphs

Scalable
Distributed
Topologies

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A graph $G(V, E)$ can be defined by a set of vertices, and a set of edges that connect pairs of vertices. For instance, a path $G(V = \{a, b, c, d\}, E = \{(a, b), (b, c), (c, d)\})$ can be made into a ring by adding one edge connecting its ends $E = E \cup \{(d, a)\}$.

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- Graphs can be directed or undirected (in which case edges are bi-directional).

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Walk, Trail, Path

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Walk Edges and vertices can be repeated

Trail Only vertices can be repeated

Path No repeated vertices or edges

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More topologies

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- Complete Graph. Each pair of vertices has an edge connecting them.

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- Complete Graph. Each pair of vertices has an edge connecting them.
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- Complete Graph. Each pair of vertices has an edge connecting them.
- Connected Graph. There is a path between any two nodes.
- Star. A “central” vertice and many leaf nodes connected to center

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- Planar Graph. Vertices and edges can be drawn in a plane and no two edges intersect. E.g. Rings and Trees are planar.

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In a network context, graphs with cycles allow multi-path routing. This can be more robust but data handling can become more complex. Thus, distributed algorithms often construct trees to avoid cycles, while others try to work under multi-path.

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More concepts

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- Connected Component. Maximal connected subgraph of G .

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- Connected Component. Maximal connected subgraph of G .
- Degree of v_i . Number of adjacent vertices to v_i . In directed graphs there is in-degree and out-degree.

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- Distance $d(v_i, v_j)$. Length of the shortest path connecting those nodes.
- Eccentricity of v_i . $ecc(v_i) = \max(\{d(v_i, v_j) | v_j \in V\})$.
- Diameter. $D = \max(\{ecc(v_i) | v_i \in V\})$
- Radius. $R = \min(\{ecc(v_i) | v_i \in V\})$

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- Diameter. $D = \max(\{ecc(v_i) | v_i \in V\})$
- Radius. $R = \min(\{ecc(v_i) | v_i \in V\})$
- Center. $\{v_i | ecc(v_i) == R\}$
- Periphery. $\{v_i | ecc(v_i) == D\}$

- How big is the center of a tree?

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Questions

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- How big is the center of a tree?
- How big is the center of a path?

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Questions

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- How big is the center of a tree?
- How big is the center of a path?
- How big is the periphery of a ring? and the center?

Graphs

Questions

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- How big is the center of a tree?
- How big is the center of a path?
- How big is the periphery of a ring? and the center?
- How to compute eccentricities?

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More complex topologies

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- Random geometric. Vertices are dropped randomly uniformly into a unit square and adding edges to connect any two points within a given euclidean distance.

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- Random geometric. Vertices are dropped randomly uniformly into a unit square and adding edges to connect any two points within a given euclidean distance. Is it planar?
- Random Erdos-Renyi. $G(n, p)$ model, n nodes are connected randomly. Each edge is included with independent probability p .

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- Watts-Strogatz model. (Seen later on small world constructions).

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- Watts-Strogatz model. (Seen later on small world constructions).
- Barabasi-Albert model. Preferential attachment: the more connected a node is, the more likely it is to receive new links. Degree Distribution follows a power law.

(http://barabasilab.neu.edu/networksciencebook/download/network_science_december_ch5_2013.pdf)

Spanning Trees

Synchronous *SyncBFS* Algorithm

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Definitions:

- A directed graph is called **strongly connected** if for every pair of vertices u and v there is a path from u to v and a path from v to u .

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- Every strongly connected graph has a breadth-first directed spanning tree.

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Processes communicate over directed edges. Unique UUIDs are available, but network diameter and size is unknown.

Initial state in *SyncBFS*

- $parent = nil$
- $marked = False$ ($True$ in root node i_0)

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SyncBFS algorithm

- Process i_0 sends a *search* message in round 1.
- Unmarked processes receiving a *search* message from x do $marked = True$ and set $parent = x$, in the next round *search* messages are sent from these processes.

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Complexity

- Time: At most $diam$ rounds (depending on i_0 eccentricity).
- Message: $|E|$. Messages are sent across all edges E .

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Child Pointers

If parents need to know their offspring, processes must reply to *search* messages with either *parent* or *nonparent*.

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Termination: Making i_0 know that the tree is constructed

All processes respond with *parent* or *nonparent*. Parent terminates when all children terminate. Responses are collected from leaves to tree root.

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Applications of Breath First Spanning Trees.

Aggregation (Global Computation)

Input values in each process can be aggregated towards a sync node.
Each value only contributes once, many functions can be used:
Sums, Averages, Max, Voting.

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Leader Election

Largest *UID* wins. All process become root of their own tree and aggregate a $Max(UID)$. Each decide by comparing their own *UID* with $Max(UID)$.

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Applications of Breath First Spanning Trees.

Broadcast

Message payload m can be attached to *SyncBFS* construction ($m|E|$ message load) or broadcasted once tree is formed ($m|V|$ message load).

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Computing Diameter

Each process constructs a *SyncBFS*. Then determines *maxdist*, longest tree path. Afterwards, all processes use their trees to aggregate $\max(\text{maxdist})$ from all roots/nodes.

Complexity: Time $O(\text{diam})$ and messages $O(\text{diam} \times |E|)$.

Asynchronous setup

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We will now work on a “bare” asynchronous network model, avoiding, for now, useful abstractions like logical time and global snapshots.

System Model

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The lack of helping tools is compensated by a “generous” system model:

Faults

No faults.

Channels

Reliable FIFO send/receive channels.

Reliable FIFO send/receive channels

Automaton

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Signature:

Input: $send(m)_{i,j}, m \in M$

Output: $receive(m)_{i,j}, m \in M$

States:

$queue = \langle \rangle$

Transitions:

$send(m)_{i,j}$

Effect:

$queue := queue + \langle m \rangle$

$receive(m)_{i,j}$

Precondition:

$queue.head = m$

Effect:

$queue.pophead()$

Reliable FIFO send/receive channels

Allowed trace behaviour

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Let β be a sequence of actions, and $cause()$ a function mapping each receive event $e \in \beta|_{receive}$ to a preceding send event $s \in \beta|_{send}$ such that:

- 1 $\forall receive(x) \in \beta|_{receive}: cause(receive(x)) = send(y) \Rightarrow x = y.$
Messages don't come out of the blue.

Reliable FIFO send/receive channels

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- 2 $cause()$ is surjective. For every $send$ there is a mapped $receive$.
Messages are not lost.

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- 3 $cause()$ is injective. For every $receive$ there is a distinct $send$.
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- 3 $cause()$ is injective. For every $receive$ there is a distinct $send$.
Messages are not duplicated.
- 4 $receive <_{\beta} receive' \Rightarrow cause(receive) <_{\beta} cause(receive')$. Order is preserved.

Spanning Trees

AsynchSpanningTree automaton for node i

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Signature:

Input: $receive("search")_{i,j}$

$j \in nbrs$

Output: $send("search")_{i,j}$

$j \in nbrs$

Output: $parent(j)_i$

$j \in nbrs$

Transitions:

$send("search")_{i,j}$

Precondition: $sendto(j) = yes$

Effect: $sendto(j) := no$

$receive("search")_{j,i}$

Effect:

if $i \neq i_0$ and $parent = null$ then

$parent := j$

for all $k \in nbrs \setminus \{j\}$ do

$sendto(k) := yes$

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Channel automaton

Consumes $send("search")_{f,t}$ and produces $receive("search")_{f,t}$ in reliable FIFO order.



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AsynchSpanningTree vs *SynchBFS*

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While *AsynchSpanningTree* looks like an asynchronous translation of *SynchBFS*, the former does not necessarily produce a breadth first spanning tree.

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Faster longer paths will win over a slower direct path when setting up *parent*.

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One can however show that a spanning tree is constructed.

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AsynchSpanningTree

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Invariant: A tree is gradually formed

In any reachable state, the edges defined by all *parent* variables form a spanning tree of a subgraph of G , containing i_0 ; moreover, if there is a message in any channel $C_{i,j}$ the i is in this spanning tree.

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Invariant: All contacts are searched

In any reachable state, if $i = i_0$ or $parent \neq null$, and if $j \in nbrs_i \setminus \{i_0\}$, then either $parent_j \neq null$ or $C_{i,j}$ contains a search message or $sendto(j)_i$ is yes.

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Leading to:

Theorem

The *AsynchSpanningTree* algorithm constructs a spanning tree in the undirected graph G .

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AsynchSpanningTree

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In asynchronous systems although time is unbounded it is practical to assume a upper bound on time taken to execute a process effect, time l , and time taken to deliver a message in channel, time d .

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Complexity

- Messages are $O(|E|)$.
- Time is $O(diam(l + d))$.

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Although a tree with height h , such that $h > diam$, can occur it only occurs if it does not take more time than a tree with $h = diam$.

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- Messages are $O(|E|)$.
- Time is $O(diam(l + d))$.

Although a tree with height h , such that $h > diam$, can occur it only occurs if it does not take more time than a tree with $h = diam$.

Faster long paths must be faster!

Spanning Trees

AsynchSpanningTree

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Child pointers and Broadcast

If nodes report *parent* or *nonparente* one can build a tree that broadcasts.

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No, because a fast path is not always fast. Complexity is $O(h(I + d))$, at most $O(n(I + d))$, where $n = |V|$.

Broadcast with Acks

Its is possible to build a *AsynchBcastAck* algorithm that collects acknowledgements as the tree is constructed. Upon incoming broadcast messages each node Acks if they already know the broadcast and Acks to parent once when all neighbours Ack to them.

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Leader Election with *AsynchBcastAck*

This algorithm includes termination and if all nodes initiate it and report their UIDs it can be used for Leader Election with unknown diameter and number of nodes.

Epidemic Broadcast Trees

Plumtree protocol

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- Gossip broadcast
 - + highly scalable and resilient
 - excessive message overhead
- Tree-based broadcast
 - + small message complexity
 - fragile in the presence of failures

Can we get the best of both worlds?

Epidemic Broadcast Trees

Gossip strategies

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- Eager push. Nodes immediately forward new messages
- Pull. Nodes periodically query for new messages
- Lazy push. Nodes push new message ids and accept pulls

In lazy push, there is a separation among payload and metadata

Epidemic Broadcast Trees

Gossiping into tree

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- Nodes sample random peers into a eagerPush set
- Neighbours should be stable and TCP can be used
- Links are kept reciprocal (towards undirected graph)
- First message reception puts origin in eagerPush
- Further duplicate receptions moves source to lazyPush
- Eager push of payload and lazy push of metadata

Epidemic Broadcast Trees

Repairing a broken tree

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If the tree breaks, and graph stays connected, nodes get metadata but not payloads. This is detected by timer expiration and the metadata source in lazyPush is moved to eagerPush. Potential redundancy (due to cycles) is cleared later by the standard algorithm.

Small Worlds

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- Milgram experiment “Six degrees of separation”.
- Path lengths were calculated on sequences of letter forwardings.

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- The question was: “Why should there exist short chains of acquaintances linking together arbitrary pairs of strangers?”

Random graphs and clustering

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- Consider a graph where a given number of edges is created uniformly at random among the graph vertices. See Erdős–Rényi model.
- The resulting random graph is known to depict a low diameter and thus could support small paths. $O(\log n)$.

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- Resulting in low diameter and high clustering.

Routing in Small Worlds

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- If we flood a Watts and Strogatz graph we will stumble on a short route between to arbitrary points. A global observer could also pinpoint a $O(\log N)$ path.
- But, can we pick a path with local knowledge and a distance metric?

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- Long range contacts can be tuned to become more clustered in the vicinity. The target is to have uniformity across all distance scales, a property found in DHT designs like Chord, and locally find $O(\log^2 N)$ routes.

Uniformity across distance scales

Pieter Bruegel the Elder - The Hunters in the Snow

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