CS244b – Distributed Systems

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Stanford University

Outline

1. Administrivia

2. Remote procedure call

3. Consensus in asynchronous systems

Administrivia

- **Class web page:** http://cs244b.scs.stanford.edu/
  - All handouts, lecture notes are on line
- **Please join edstem**
  - Can ask questions by noon on lecture day to influence lecture
  - Also find teammates, delve into topics with more detail, etc.
- **Each class will involve discussing papers**
  - Print, read the papers before class
  - Class participation is required (or edstem if you have special dispensation not to attend)
  - You may get cold-called if you haven't participated in a few lectures
  - I will post discussion notes after lecture
- **Zoom should work for SCPD (but please mute your mic)**
- **Please bring an** 8.5" × 11" **name card to lecture**
- **Staff mailing list:** cs244b-staff@scs.stanford.edu
  - Please email all staff rather than individual members

Assignments

- **Read papers before class**
  - Don't take this lightly—should spend several hours reading
- **Final project**
  - Perform a small research project in teams of 1–4 students
  - Use ideas from papers we've discussed in class
- **Schedule:**
  - April 11: Form team (can use mailing list to find teammates)
  - April 18: Schedule meeting with me or CA to discuss project
  - Shortly after meeting: project title and one paragraph
  - May 27: Submit git repository, and revised title/paragraph
  - June 3: Submit paper on project (up to 6 pages)
  - June 7: Project presentations/demos (12:30pm–late)
- **Grading primarily based on final project**
  - Adjusted based on class participation

Why study distributed systems?

- Most real systems are actually distributed systems
- **If you want fault-tolerance or scalability**
  - Must replicate or shard across multiple machines
- **If you want systems that span administrative realms**
  - Web sites, peer-to-peer systems, communication systems

Class topics

- Distributed programming models
- Dealing with failure, including Byzantine failure
- Scalability
- Techniques: Consensus, Replication, Consistency…
- Case studies: production systems at Google, Amazon, …
- A few Blockchain mechanisms

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Remote procedure call (RPC)

- **Procedure calls are a well-understood mechanism**
  - Transfer control and data on single computer
- **RPC's goal is to make distributed programming look like as much as possible like normal programming**
  - Code libraries provide APIs to access functionality
  - RPC servers export interfaces accessible through local APIs
  - See [Birrell] for good description of one implementation
- **Implement RPC through request-response protocol**
  - Procedure call generates network request to server
  - Server return generates response
- **Good example of how distributed systems differ. . .**

Procedure vs. RPC

- **Consider the following ordinary procedure:**

```
bool add_user(string user, string password);
```

- **Possible return values:** `true`, `false`
- **Now say you have an RPC version**
  - Must somehow set up connections, bind to server, think about authentication, etc., but ignore all that for now
- **What are the possible return values of** `add_user` **RPC?**

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- **What are the possible return values of** `add_user` **RPC?**
  1. `true`
  2. `false`
  3. "I don't know"

RPC Failure

- **Normal procedure call has fate sharing**
  - Single process: if callee fails, caller fails, too
- **RPC introduces more failure modes**
  - Machine failures at only one end (caller/callee)
  - Communication failures
- **Result: RPCs can return "failure" instead of results**
- **What are the possible outcomes after failure?**
  - Procedure did not execute
  - Procedure executed once
  - Procedure executed multiple times
  - Procedure partially executed
- **Many systems aspire to "at most once semantics"**

Implementing at most once semantics

- **Danger: Request message lost**
  - Client must retransmit requests when it gets no reply
- **Danger: Reply message may be lost**
  - Client may retransmit previously executed request
  - Okay if operations are idempotent, but many are not (e.g., process order, charge customer, . . .)
  - Server must keep "replay cache" to reply to already executed requests
- **Danger: Server takes too long to execute procedure**
  - Client will retransmit request already in progress
  - Server must recognize duplicate—can reply "in progress"

Server crashes

- **Danger: Server crashes and reply lost**
  - Can make replay cache persistent—slow
  - Can hope reboot takes long enough for all clients to fail
- **Danger: Server crashes during execution**
  - Can log enough to restart partial execution—slow and hard
  - Can hope reboot takes long enough for all clients to fail
- **Can use "cookies" to inform clients of crashes**
  - Server gives client cookie which is time of boot
  - Client includes cookie with RPC
  - After server crash, server will reject invalid cookie

Parameter passing

- **Trivial for normal procedure calls**
- **RPC must worry about different data representations**
  - Big/little endian
  - Size of data types
- **RPC has no shared memory**
  - No global variables
  - How to pass pointers
  - How to garbage-collect distributed objects
- **How to pass unions over RPC?**

Interface Definition Languages

- **Idea: Specify RPC call and return types in IDL**
- **Compile interface description with IDL compiler. Output:**
  - Native language types (e.g., C/C++/Java/go/etc. structs)
  - Code to *marshal* (serialize) native types into byte streams
  - *Stub* routines on client to forward requests to server
- **Stub routines handle communication details**
  - Helps maintain RPC transparency, but…
  - Still have to bind client to a particular server
  - Still need to worry about failures

C++ RPC-related systems in use today

- **XML or JSON over HTTP – no IDL, hard to parse**
- **Cereal – C++11 structure serializer**
- **Google protobufs + gRPC, Apache Thrift**
  + Compact encoding, defensively coded (protobufs)
  + Good support for incrementally evolving messages
  – Complex encoding, no canonical representation
- **Apache Avro – self-describing messages contain schema**
- **Cap’n Proto, Google FlatBuffers**
  + Same representation in memory and on wire, very fast
  – Less mature, non-deterministic wire format, bigger attack surface
- **XDR (+ RPC) – used by Internet standards such as NFS**
  + Simple, good features (unions, fixed- and variable-size arrays, . . .)
  – Big endian, binary but rounds everything to multiple of 4 bytes

“Homework”

- **Write and run a simple distributed application using RPC**
  - Use any of the technologies from previous slide
  - Or any other RPC system you like
- **We won’t grade it, but it will help with your project**

Case study: XDR

```
enum MyEnum { NO, YES, MAYBE };

struct MyMessage {
  string name<16>;   /* up to 16 characters */
  string desc<>;     /* up to 2^32-1 characters */
  opaque cookie[8]; /* 8 bytes (fixed) */
  opaque sig<16>;    /* 0-16 bytes (variable-length) */
  unsigned int u;    /* Unsigned 32-bit integer */
  hyper ii;          /* Signed 64-bit integer */
  MyEnum me;         /* Another user-defined type */
  int ia[5];         /* Fixed-length array */
  int iv<>;          /* Variable length array */
  int iv1<5>;        /* Up to 5 ints */
  MyMessage *mep;    /* optional MyMessage (or NULL) */
};

typedef MyMessage *OptionalMyStruct;
```

XDR base types

- **All numeric values encoded in big-endian order**
- int, unsigned [int], **all** enums**: 4 bytess**
- bool: **equivalent to** "enum bool { FALSE, TRUE }"
- hyper, unsigned hyper: **8 bytes**
- float, double, quadruple: **4-, 8-, or 16-byte floating point**
- opaque bytes[Len] **(fixed-size)**
  - Encoded as content + 0–3 bytes padding to make size multiple of 4
- string s<MaxLen>, opaque a<MaxLen> **(variable-size)**
  - 4-byte length + content + (0–3 bytes) padding

XDR containers and structs

- **(Fixed) arrays –** `MyType var[`n`]`
  - Encoded as n copies of `MyType`
- **Vectors –** `MyType var<>` **or** `MyType var`<n>
  - Can hold variable number (0–n) `MyType`s
  - Encoded as 4-byte length followed by that many
  - Empty maximum length means maximum length $2^{32} - 1$ `MyType`s
- **Optional data –** `MyType *var`
  - Encoded exactly as `MyType var<1>`
  - Note this means single "present" bit consumes 4 bytes
- `struct` **– each field encoded in turn**

XDR `union` types

```
union type switch (simple_type which) {
  case value_A:
    type_A varA;
  case value_B:
    type_B varB;
  /* ... */
  default:
    void;
};
```

- **Must be discriminated, unlike C/C++**
- `simple_type` **must be** `[unsigned] int`, `bool`, **or** `enum`
- **Wire representation:**
  - 4-bytes for `which` + encoding of selected case
  - Special `void` type encoded as 0 bytes

Demo

```
git clone http://cs244b.scs.stanford.edu/xdrdemo.git
```

- **References for demo**
  - C++ RPC library: `https://github.com/xdrpp/xdrpp`
  - Go RPC library: `https://github.com/xdrpp/goxdr`
  - XDR specification: RFC4506
  - RPC specification: RFC5531

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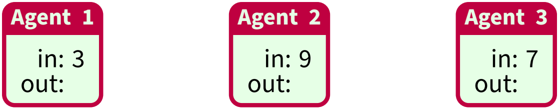
Asynchronous systems[1]

- **A theoretical model for distributed systems**
  - Consists of a set of agents exchanging messages
  - No bound on message delays
  - No bound on the relative execution speed of agents
  - For convenience, model internal events such as timeouts as special messages, so the “network” controls all timing
- **Can’t distinguish failed agent from slow network**
- **Idea of model is to be conservative**
  - Want robustness under any possible timing conditions
  - E.g., say backhoe tears fiber, takes a day to repair
  - Could see messages delays a *billion* times more than usual

[1] Unrelated to “asynchronous IO” as used in event-driven systems.

The consensus problem



- **Goal: For multiple agents to agree on an output value**

⟶ **Each agent starts with an input value**
  - Agents' inputs may differ; any agent's input is okay to output
- **Agents communicate following some *consensus protocol***
  - Use protocol to agree on one of the agent's input values
- **Once decided, agents output the chosen value**
  - Output is write-once (an agent cannot change its value)

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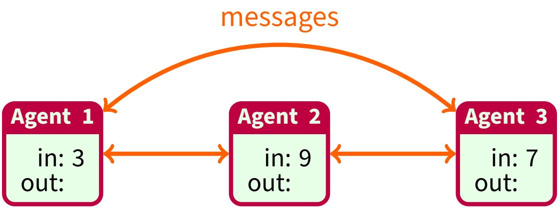

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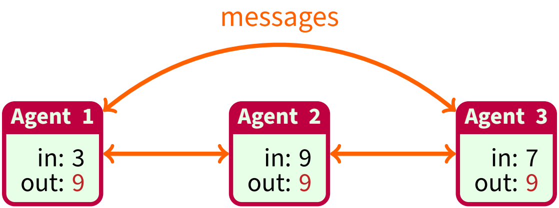

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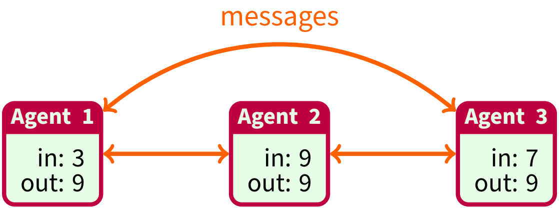
Properties of a consensus protocol

- **A consensus protocol provides *safety* if...**
  - Agreement – All outputs produced have the same value, and
  - Validity – The output value equals one of the agents' inputs
- **A consensus protocol provides *liveness* if...**
  - Termination – Eventually non-failed agents output a value
- **A consensus protocol provides *fault tolerance* if...**
  - It can survive the failure of an agent at any point
  - *Fail-stop* protocols handle agent crashes
  - *Byzantine-fault-tolerant* protocols handle arbitrary agent behavior

Theorem (FLP impossibility result)

No deterministic consensus protocol guarantees all three of safety, liveness, and fault tolerance in an asynchronous system.

Bivalent states



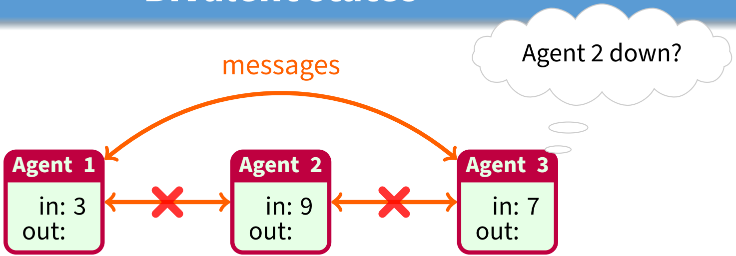
→ **Recall agents chose value 9 in last example**

- **But a network outage could look like agent 2 failing**
- **If fault-tolerant, Agents 1 & 3 might decide to output 7**
- **Once network back, Agent 2 must also output 7**

Definition (Bivalent)

An execution of a consensus protocol is in a bivalent state when the network can affect which value agents choose.

Bivalent states



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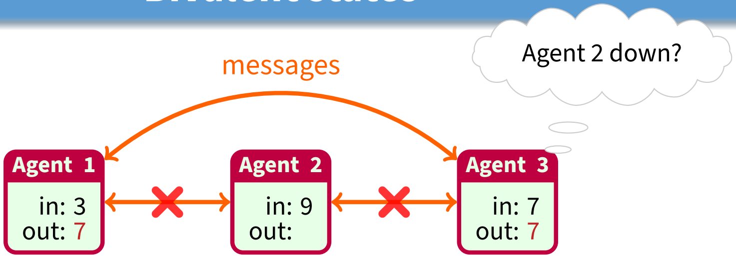

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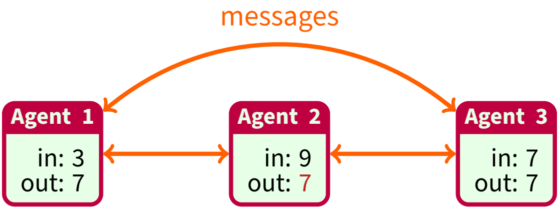

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Univalent and stuck states

Definition (Univalent, Valent)

An execution of a consensus protocol is in a univalent state when only one output value is possible. If that value is i, call the state i-valent.

Definition (Stuck)

An execution of a [broken] consensus protocol is in a stuck state when one or more non-faulty nodes can never output a value.

- **Recall output is write once and all outputs must agree**
  - Hence, no output is possible in bivalent state
- **If an execution starts in a bivalent state and terminates, it must at some point reach a univalent state**

FLP intuition

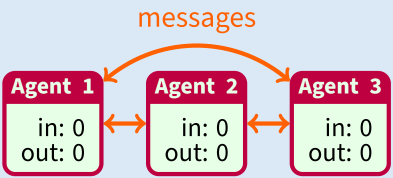
- **Consider a terminating execution of a bivalent system**
- **Let *m* be last message received in a bivalent state**
  - Call *m* the execution's deciding message
  - Any terminating execution requires a deciding message
- **Suppose the network had delayed *m***
  - Other messages could cause transitions to other bivalent states
  - Then, receiving *m* might no longer lead to a univalent state
  - In this case, we say *m* has been neutralized

Overview of FLP proof.

1. **There are bivalent starting configurations**
2. **The network can neutralize any deciding message**
3. **Hence, the system can remain bivalent in perpetuity** □

There exists a bivalent state

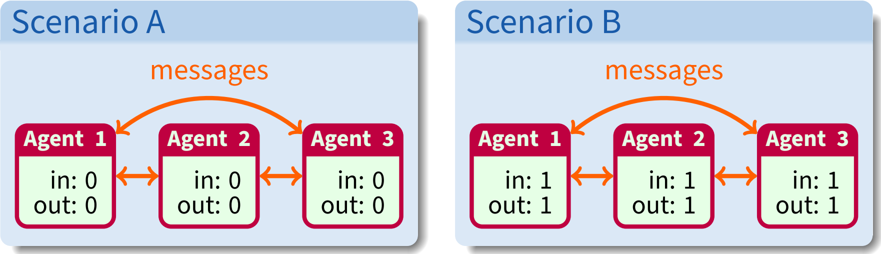
Scenario A



- **Assume you could have liveness with an agent failure**

→ **If all inputs 0, correct agents must eventually output 0**
  - Similarly, if all inputs 1, correct agents must eventually output 1
- **Now say we start flipping one input bit at a time**
- **Find 0- and 1-valent states differing at only one input**
  - Suppose node with this differing input fails
  - By assumption, the system nonetheless reaches consensus
  - Hence output depends on network; at least one state was bivalent

There exists a bivalent state



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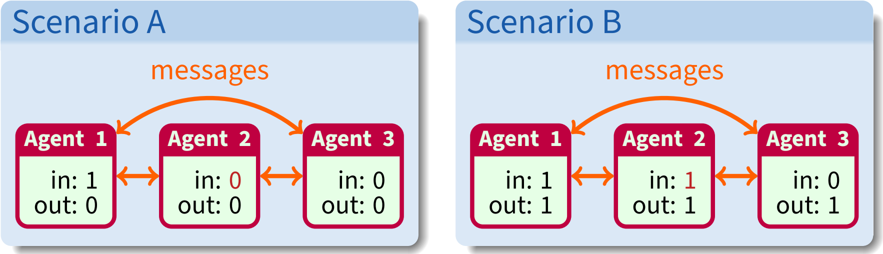

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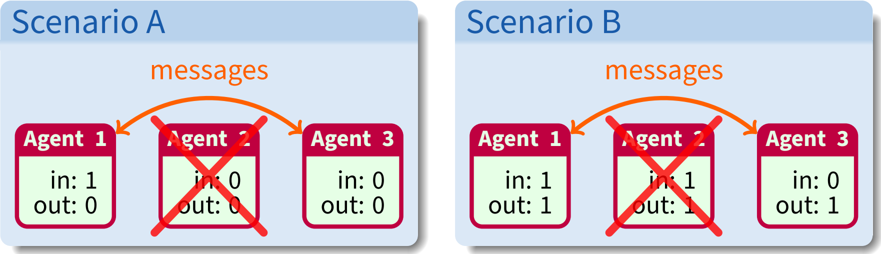

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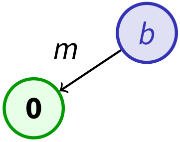
Any message can be neutralized



- → **Let *m* be a deciding message for value 0 from state *b***
  - Let's assume *m* cannot be neutralized and derive a contradiction
- **Consider a message schedule from *b* to a 1-valent state**
  - If *m* is on the path, it leads to a bi-valent state (so neutralized)
  - If *m* is not on the path, append it to the (1-valent) path
- **Apply *m* to each node on the path**
  - Either *m* will lead to a bi-valent state (neutralized), or it will produce differing univalent states on adjacent nodes c_0 and c_1

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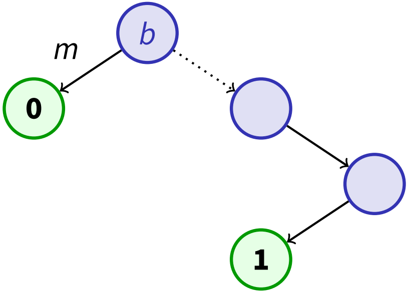

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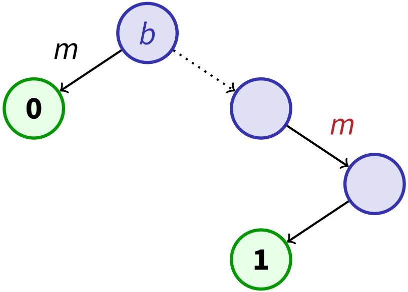

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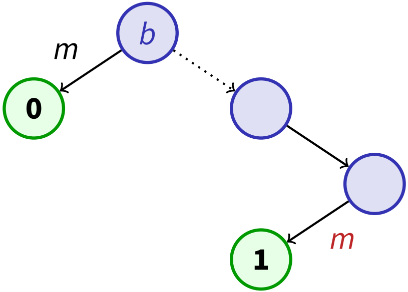

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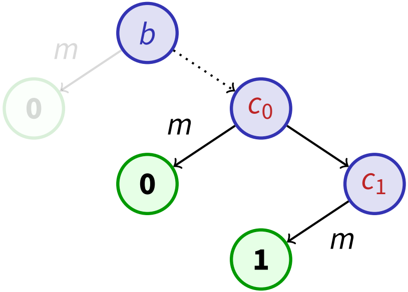

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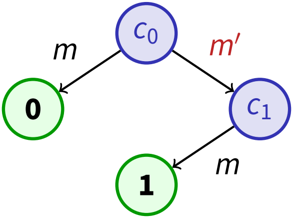

⟶ **Let m' be the message that transitions between c_0 and c_1**

- **If m, m' received by different agents, order won't matter**
  - But if delivering *both* messages yields a 1-valent state, delivering just m can't yield a 0-valent state
- **Hence, m and m' were addressed to the same agent A, making order significant**
- **Yet if A slow after c_0, system must terminate without it**

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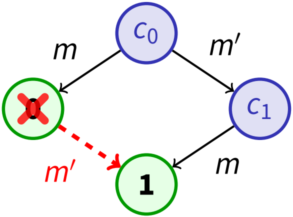

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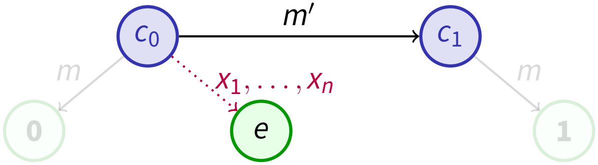

⟶ **Consider a run that terminates without A**

- Let $x_1, \ldots, x_n$ be the messages received (by nodes other than A)
- Let e be a univalent state reached during the run

- **Deliver $x_1, \ldots, x_n$ to terminating states after m**
  - Since ms and xs received by different nodes, can re-order
  - Means e not univalent (leads to both 0- and 1-valent states)!
- **Contradiction means m must be neutralized somewhere**

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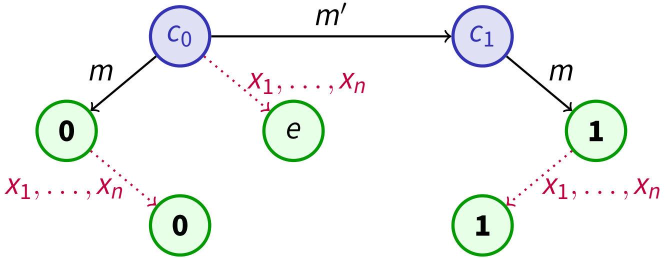

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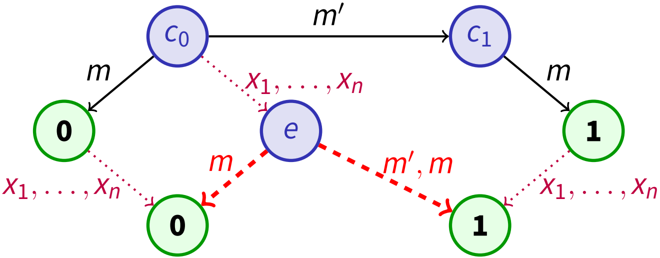
  - Let $x_1, \ldots, x_n$ be the messages received (by nodes other than A)
  - Let e be a univalent state reached during the run

⟶ **Deliver** $x_1, \ldots, x_n$ **to terminating states after** m

  - Since ms and xs received by different nodes, can re-order
  - Means e not univalent (leads to both 0- and 1-valent states)!

- **Contradiction means** m **must be neutralized somewhere**

Any message can be neutralized



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Coping with FLP

- **This class will cover**
  - Many systems that require consensus
  - Many techniques for consensus
- **Safety is generally pretty important**
- **But can reasonably weaken liveness requirement**
  - Termination not guaranteed doesn't mean it won't happen
  - If your algorithm prevents completely stuck states
    …can often make it terminate "in practice"
- **Can weaken asynchronous system assumption**
- **Can make agents non-deterministic**
  - Have all nodes flip a coin to pick value—might all pick same value
  - Make it intractable for network to "guess" pathological delivery 100% accurately in perpetuity