Distributed Systems Theory for Mere Mortals





Hello!

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- Leading open source Java IMDG
- Distributed Java collections, JCache, HD store,
- Distributed computation and messaging
- Embedded or client-server deployment
- Integration modules & cloud friendly



Hazelcast as a Distributed System

- Scale up & scale out \bigcirc
- Distributed from day one \bigcirc
- Dynamic clustering and elasticity
- Data partitioning and replication \bigcirc
- Fault tolerance



- Collection of entities trying to solve a common problem
 - Communication via passing messages
 - Uncertain and partial knowledge
- We need distributed systems mostly because:
 - Scalability
 - Fault tolerance



- Independent failures
- Non-negligible message transmission delays
- Unreliable communication



- System models come into play.
 - Interaction models
 - Failure modes
 - Notion of time
- Consensus Problem
- CAP Principle



- Synchronous
- Partially synchronous
 - Asynchronous

Hazelcast embraces the partially-synchronous model.
OperationTimeoutException



- 👊 💿 Crash-stop
- 👊 💿 Omission faults
- 👊 💿 Crash-recover
- 💄 👊 💿 Arbitrary failures (Byzantine)
 - Hazelcast handles crash-recover failures by making them look like crash-stop failures.



- Time is often used to order events in distributed algorithms.
- Physical timestamps
 - LatestUpdateMapMergePolicy in Hazelcast
- Clock drifts can break *latest update wins*
- Google TrueTime



- Logical clocks (Lamport clocks)
 Local counters and communication
- Defines *happens-before* relationship.
 (i.e., *causality*)

Hazelcast extensively uses it along with *primary-copy* replication.



- Inferring *causality* by comparing timestamps.
- *Vector clocks* are used to infer *causality*.
 - Dynamo-style databases use them to detect conflicts.

Lamport clocks work fine for Hazelcast because there is only a single node performing the updates.



- The problem of having a set of processes agree on a value.
 - Leader election, state machine replication, strong consistency, distributed transactions, ...
- Safety
- Liveness



- In the asynchronous model, distributed consensus may not be solved within bounded time if at least one process can fail with crash-stop.
- It is because we cannot differentiate between a crashed process or a slow process.

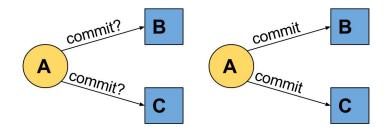


Unreliable Failure Detectors

- Local failure detectors which rely on timeouts and can make mistakes.
- Two types of mistakes:
 - suspecting from a running process \Rightarrow **ACCURACY**
 - not suspecting from a failed process \Rightarrow **COMPLETENESS**
- Different types of failure detectors.



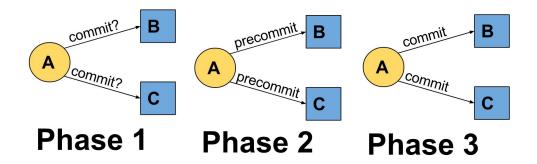
 2PC preserves *safety*, but it can lose *liveness* with *crash-stop* failures.



Phase 1 Phase 2



 3PC tolerates crash-stop failures and preserves liveness, but can lose safety with network partitions or crash-recover failures.





Majority Based Consensus

- Availability of majority is needed for *liveness* and *safety*.
 - *2f* + *1* nodes tolerate failure of *f* nodes.
- Resiliency to crash-stop, network partitions and crash-recover.
- Paxos, Zab, Raft, Viewstamped Replication



We have 2PC and 3PC in Hazelcast, but not majority based consensus algorithms.

• Consensus systems are mainly used for achieving strong consistency.

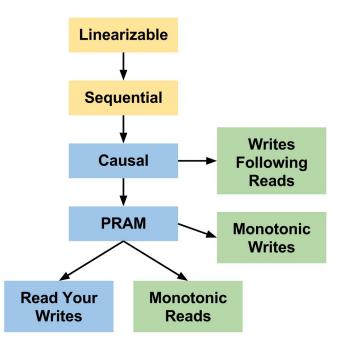


- Proposed by Eric Brewer in 2000.
 - Formally proved in 2002.
- A shared-data system cannot achieve perfect consistency and perfect availability in the presence of network partitions.
 - AP versus CP
- Widespread acceptance, and yet a lot of criticism.



Consistency and Availability

- Levels of consistency:
 Data-centric (CP)
 Client-centric (AP)
- Levels of availability:
 High availability
 Sticky availability





Hazelcast & CAP Principle

Hazelcast is AP with primary-copy & async replication.

primary-copy

strong consistency on a stable cluster

async replication

high throughput

sticky availability

possibility of losing consistency on failures



- A lot of variations in the abstractions and models.
- Learn the fundamentals, the rest will change anyway.



