

Warning!

- Material is deceptively simple
- Looks obvious once you've thought about it
- But it took several years (and Lamport) to do the thinking
- And even the authors made errors....
- Just pay attention to the basic ideas, will get more detailed later in the course

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Make Example			
UTC	C1	C2	
File compiled 10	5	15	
File edited 15	10	20	
Make initiated 20	15	25	
File.c on 1: 10	File.o on 2: 15		
Make does not recompile file			6

What Does Make Need?

- Machine needs to know if time of compilation is later than time of last edit.
- Ordering, not absolute time.
- Could be easily provided at the application level
 Annotate file.o with timestamp of file.c

Assumptions

- Each machine has local clock
- No guarantee of accuracy, but never runs backwards
- Clocks on different machines will eventually differ substantially unless adjustments are made

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Terminology

- Consider a clock with readings C(t), where t is UTC
- If C(t) = R x t + A then (different from book)
 A = offset
 R = skew
- If A or R change, that's drift
- Different clocks have different A, R

Adjusting Clocks • Never make time go backwards! - Would mess up local orderings • If you want to adjust a clock backwards, just slow it down for a bit

Aside #1: How Good are Clocks?

- Ordinary quartz clocks: 10⁻⁶ drift-seconds/second
- High-precision quartz clocks: 10⁻⁸
- International Atomic Time (IAT): 10⁻¹³
- GPS: 10⁻⁶ (why not just use GPS?)
- Computer clocks are lousy!

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Clock Synchronization (Berkeley)

- Time master polls clients (has no UTC)
- Gets time from each client, and averages
- Sends back message to each client with a recommended adjustment
- · What advantages does this algorithm have?

Aside #2: Internet vs LAN Synchronizing at Internet scale is very different than synchronizing on a LAN Delays more variable Packet drops more likely

Network Time Protocol (NTP)

- Time service for the Internet
 Synchronizes clients to UTC
- Primary servers connected to UTC source
- Secondary servers are synchronized to primary servers
- Clients synchronize with secondary servers

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NTP (2)

- Reconfigurable hierarchy
 Adapts to server failures, etc.
- Multiple modes of synchronization
- Multicast (on LAN)
 - Server-based RPC
 - Symmetric (the fancy part!)
 - Pairs exchange messages
 - · Attempt to model skew, offset
 - Signal processing to average out random delays
 - 10s of milliseconds over Internet

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Aside #3: Sensornet Synchronization Leverages properties of broadcast: Multiple receivers Multiple receivers Minimal propagation time Beacon sends out messages Nodes receiving them compare timestamps Can extend to global synchronization Neat mathematics....(clocks as rubber bands) On order of microseconds, not milliseconds Why is this important?

Logical Clocks

- Who cares about time anyway?
- Ordering is usually enough
- · What orderings do we need to preserve?













Aside #3: The Debate!

- There is a dispute about whether one needs highly synchronized primitives like totally ordered multicast
 - Recall, make problem handled by app-specific techniques
- Some contend that you should not embed heavyweight time ordering when most events don't need to be ordered
 - Only order important events using app-specific methods

Vector Timestamps

- L(A) < L(B) doesn't tell you that A came before B
- Only incorporates intrinsic causality, ignores any relationship with external clocks or external events
- Vector timestamps have the property that
 V(A) < V(B) then A causally precedes B

Vector Timestamps (2)

- V_I[I]: number of events occurred in process I
- V_I[J] = K: process I knows that K events have occurred at process J
- All messages carry vectors
- When J receives vector v, for each K it sets
 V_J[K] = v[K] if it is larger than its current value

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Vector Timestamps (3)

- If the vector associated event A is less than that associated with B, then A preceded B.
- · This comparison is element by element
- Two vectors are "concurrent" if neither dominates the other
 (1,5,1) vs (5, 1, 5)
 - (,-,) (-, , -)
- Why does this work?

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Termination

- Need distributed snapshot with no messages in flight
- Send "continue" message when finished with all channels, but not all have sent "done"
- Send "done" when all channels have sent "done" or when no other messages have been received since taking local state

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Comments

- Few of these algorithms work at scale, with unreliable messages and flaky nodes
- What do we do in those cases?