When is Recoverable Consensus Harder Than Consensus?

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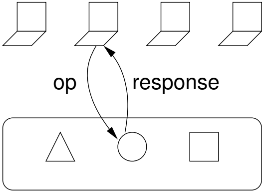
Context

Classical shared memory



processes

shared memory
with objects of
various types

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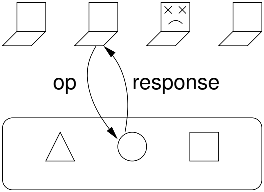
Classical shared memory
Wait-free algorithms



asynchronous processes

shared memory with objects of various types

Permanent crash failures

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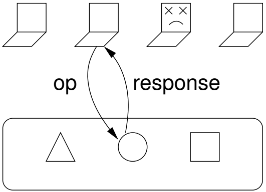
Classical shared memory
Wait-free algorithms

Non-volatile shared memory
Recoverable algorithms



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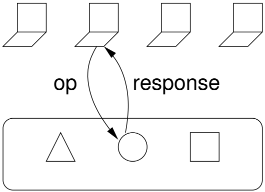

Permanent crash failures

Crash-recovery failures

-erase *local* memory of process (including programme counter)

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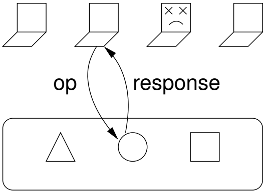

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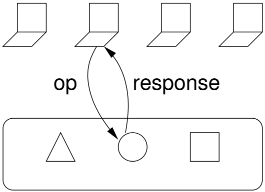

Crash-recovery failures

-erase *local* memory of process
(including programme counter)

$$\text{Algorithm } A \xrightarrow{\;?\;} \text{Algorithm } A'$$

Consensus

Consensus Problem

Each process has an input value and must output a value.

- Each output is the input of some process
- No 2 outputs differ
- If a process takes enough steps without crashing, it outputs a value

Recoverable Consensus

Consensus in context of crash-recovery failures

Recoverable Consensus Problem (RC) [Golab SPAA 2020]

Each process has an input value and must output a value.

- Each output is the input of some process
- No 2 outputs differ (including 2 outputs of 1 process)
- If a process takes enough steps between crashes, it outputs a value

Consensus Hierarchy

C#(T) = consensus number of type T

maximum number of processes that can solve wait-free consensus using objects of type T and registers
tolerating permanent crashes

RC#(T) = recoverable consensus number of type T

maximum number of processes that can solve recoverable consensus using objects of type T and registers
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Consensus numbers tell us about wait-free implementations [Herlihy 1991]

Universality

$C\#(T) \geq n \Rightarrow T$ implements *every* object for n processes

Non-implementability

$C\#(T) < C\#(T') = n$
$\Rightarrow T$ cannot implement T' for n processes.

Analogous results for $RC\#(T)$.
[Berryhill, Golab, Tripunitara OPODIS 2015; this work]

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Significance of Recoverable Consensus

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Key Question

$RC\#(T) \leq C\#(T)$

Any RC algorithm also solves consensus.
So RC is at least as hard as consensus.

Question

Is RC (much) harder than consensus?
Can $RC\#(T)$ be (much) smaller than $C\#(T)$?

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System-wide crash-recovery failures

$RC\#(T) = 2 \Leftrightarrow C\#(T) = 2.$ [Golab 2020]

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Independent crash-recovery failures:

- With *known bound* on number of failures: $RC\#(T) = C\#(T)$. [Golab 2020]
- Necessary condition for $RC\#(T) \geq 2$. [Golab 2020]

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- Necessary condition for $RC\#(T) \geq 2.$ [Golab 2020]
  We characterize readable types with $RC\#(T) = n$ for all n.
  [Ovens Tue] completed proof that characterization is exact.

Main Results

Focus on readable objects, independent failure model.

We define n-recording property of shared object types.

$$
\begin{array}{c}
n\text{-recording} \\
\Downarrow \\
n\text{-proc RC solvable} \\
\Downarrow \\
(n-1)\text{-recording}
\end{array}
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n-recording

$\Downarrow$

n-proc RC solvable

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$(n-1)$-recording

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$(n-1)$-proc RC solvable

$\Downarrow$

$(n-2)$-recording

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$(n-2)$-proc RC solvable

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$$\begin{tikzcd}[arrows=Rightarrow]
n\text{-recording} \arrow[d] & \\
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$C\#(T) - 2 \leq RC\#(T) \leq C\#(T)$

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$\Downarrow$ $\Uparrow$ [Ovens Tue]

n-proc RC solvable $\Rightarrow$ n-process consensus solvable

$\Updownarrow$ [Ruppert PODC 1997]

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$(n-1)$-recording $\not\Leftarrow$ n-discerning

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$(n-1)$-proc RC solvable

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$(n-2)$-recording $\Leftarrow$

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$$C\#(T) - 2 \leq RC\#(T) \leq C\#(T)$$

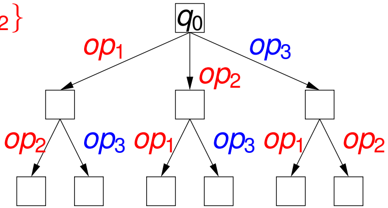
n-recording Property: First Attempt

- Pick a starting state q_0.
- Divide n processes into two teams *Red* and *Blue*.
- Assign an operation op_i to each process p_i.

Look at states reached from q_0 by permutations of $op_1, \ldots, op_n$.

Example: 3 processes p_1, p_2, p_3.

$Red = \{p_1, p_2\}$
$Blue = \{p_3\}$



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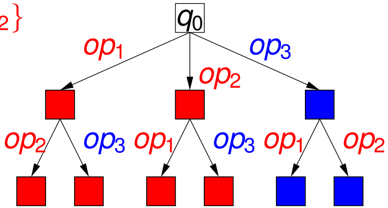

State should *record* which team did the *first* operation after q_0.

- Red states are disjoint from blue states
- q_0 is neither red nor blue

Sufficiency of n-recording Property

Team RC problem

Same as RC with constraint: each team gets a common input

Theorem

An n-recording type T can solve n-process team RC.

Proof.

Use object O of type T (initially q_0) and one register per team

Decide(v)
  write v into my team's register
  if O's state is q_0 then perform op_i on O
  read O and determine which team accessed O first
  output value from that team's register

If red process accesses O first, state stays red forever.

If blue process accesses O first, state stays blue forever. □

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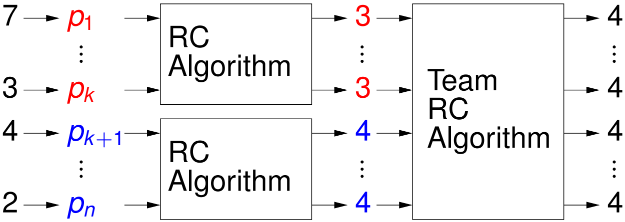
Sufficiency: Solving RC using team RC



[Neiger 1995, Ruppert 1997]

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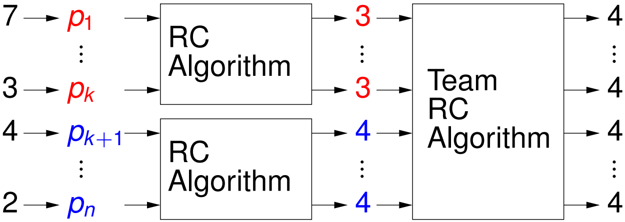

Solve smaller RC instances recursively.
$\rightarrow$ Yields a tournament algorithm

[Neiger 1995, Ruppert 1997]

Refining the Condition

Example: 3 processes p_1, p_2, p_3.

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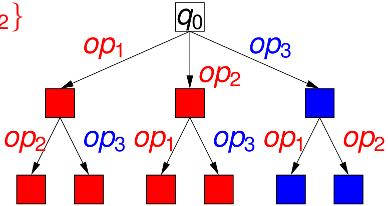

- Red states are disjoint from blue states
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- q_0 *can* be red *if* there is only one blue process
- q_0 *can* be blue *if* there is only one red process

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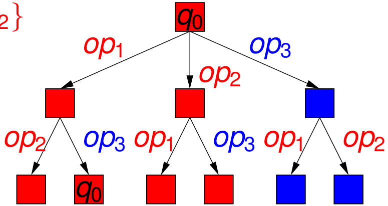

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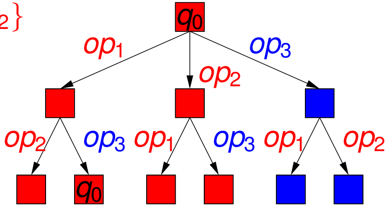

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Modified Definition Still Sufficient for Team RC

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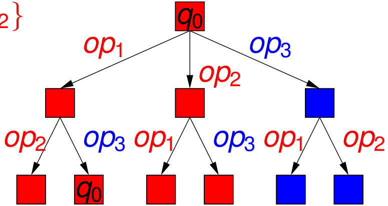

Key idea to modify team RC algorithm if q_0 is red:
p_3 performs op_3 on O only if
p_3 sees state is q_0 *and* no red process has woken up.

$\Rightarrow$ Ensures that if state of O returns to q_0, it remains red forever.

Sufficiency

Theorem (Sufficient Condition)

T is n-recording $\Rightarrow RC\#(T) \geq n$

Proof Sketch

Build team RC algorithm using n-recording object.
Use team RC in tournament to solve RC.

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Proof Sketch

Build team RC algorithm using *n*-recording object.
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Necessity

Theorem (Necessary Condition)

T *is* $(n-1)$*-recording* $\Leftarrow RC\#(T) \geq n$

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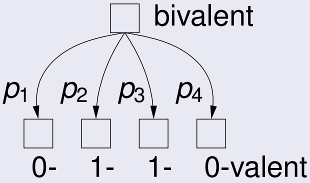
Ideas for proof

- Valency argument
- Critical configuration used to define q_0, $op_1, \ldots, op_n$, teams



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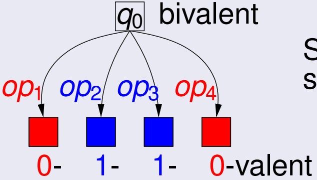

Show that these choices satisfy definition

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  Solution: Use restricted set of runs:
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  Ensures every run produces output.
- Challenge: Must construct runs that belong to this set.
  Solution: "Extra process" takes steps to enable crashes.

Main Results (Readable Types, Indep. Failures)

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$\Downarrow$ $\Uparrow$ [Ovens Tue]

n-proc RC solvable $\Rightarrow$ n-process consensus solvable

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$(n-2)$-recording $\Leftarrow$

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$(n-2)$-proc RC solvable

Corollary

$C\#(T) - 2 \leq RC\#(T) \leq C\#(T)$

Examples

Sometimes $RC\#(T) = C\#(T)$ and
sometimes $RC\#(T) < C\#(T)$.

Bonus Result: Robustness

Theorem

If RC is solvable using several readable types together, then RC is solvable using one of those types.

$RC\#(T_1, \ldots, T_k) \leq \max(RC\#(T_1), \ldots, RC\#(T_k)) + 1$

Update [Ovens Tue]:
$RC\#(T_1, \ldots, T_k) = \max(RC\#(T_1), \ldots, RC\#(T_k))$

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Old Research Directions

- Is $rcons(T) = cons(T) - 2$ for some readable type T?
- Is $rcons(T) << cons(T)$ for some non-readable type T?
- Close gap between necessary and sufficient condition.

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- Is $rcons(T) = cons(T) - 2$ for some readable type T?
  Yes. [Ovens Tue]
- Is $rcons(T) << cons(T)$ for some non-readable type T?
  Yes. [Ovens Tue]
- Close gap between necessary and sufficient condition.
  Done. [Ovens Tue]

New Research Directions

- Understand what makes recoverable consensus harder when using non-readable types.
- Consider other agreement problems in recoverable setting.
  approximate agreement, set agreement, ...
- Efficient algorithms for RC and recoverable implementations of data structures