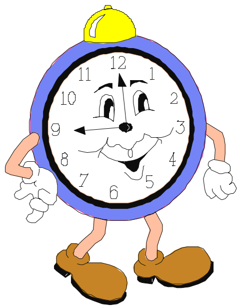
Clocks and Time

Overview

- Time service
  - requirements and problems
  - sources of time
- Clock synchronisation algorithms
  - clock skew & drift
  - Cristian algorithm
  - Berkeley algorithm
  - Network Time Protocol
- Logical clocks
  - Lamport’s timestamps

Time service

- Why needed?
  - to measure delays between distributed components
  - to synchronise streams, e.g. sound and video
  - to establish event ordering
    - causal ordering (did A happen before B?)
    - concurrent/overlapping execution (no causal relationship)
  - for accurate timestamps to identify/authenticate
    - business transactions
    - serializability in distributed databases
    - security protocols

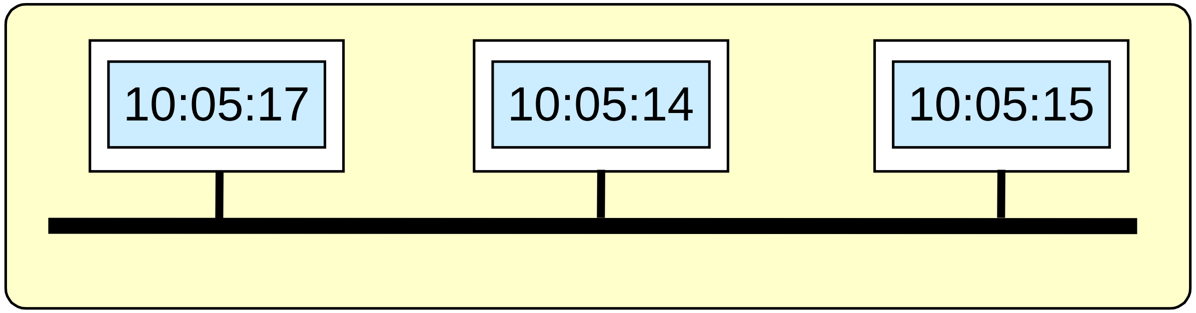


Clocks

- Internal hardware clock
  - built-in electronic device
  - counts oscillations occurring in a quartz crystal at a definite frequency
  - store the result in a counter register
  - interrupt generated at regular intervals
  - interrupt handler reads the counter register, scales it to convert to time units (seconds, nanoseconds) and updates software clock
    - e.g. seconds elapsed since 1/01/1970

Problems with internal clocks

- Frequency of oscillations
  - varies with temperature
  - different rate on different computers



- Accuracy
  - typically 1 sec in 11.6 days
- Centralised time service?
  - impractical due to variable message delays

Clock skew and drift

- Clock skew
  - difference between the readings of two clocks
- Clock drift
  - difference in reading between a clock and a nominal perfect reference clock per unit of time of the reference clock
    - typically 10^{-6} seconds/second = 1 sec in 11.6 days

Sources of time

- Universal Coordinated Time (UTC, from French)
  - based on atomic time but leap seconds inserted to keep in phase with astronomical time (Earth's orbit)
  - UTC signals broadcast every second from radio and satellite stations
    - land station accuracy 0.1-10ms due to atmospheric conditions
- Global Positioning System (GPS)
  - broadcasts UTC
- Receivers for UTC and GPS
  - available commercially
  - used to synchronise local clocks

Clock synchronisation

- External: synchronise with authoritative source of time
  - the absolute value of difference between the clock and the source is bounded above by D at every point in the synchronisation interval
  - time accurate to within D
- Internal: synchronise clocks with each other
  - the absolute value of difference between the clocks is bounded above by D at every point in the synchronisation interval
  - clocks agree to within D (not necessarily accurate time)

Clock compensation

- Assume 2 clocks can each drift at rate R msecs/sec
  - maximum difference 2R msecs/sec
  - must resynchronise every D/2R to agree within D
- Clock correction
  - get UTC and correct software clock
- Problems!
  - what happens if local clock is 5 secs fast and it is set right?
  - timestamped versions of files get confused
  - time must never run backwards!
  - better to scale the value of internal clock in software without changing the clock rate

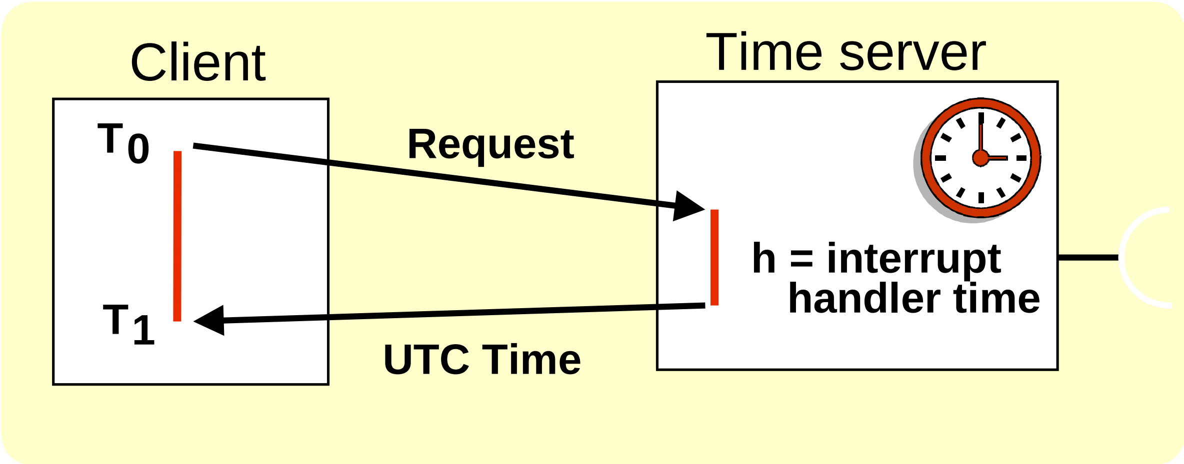
Synchronisation methods

- Synchronous systems
  - simpler, relies on known time bounds on system actions
- Asynchronous systems
  - intranets
    - Cristian’s algorithm
    - Berkeley algorithm
  - Internet
    - The Network Time Protocol

Synchronous systems case

- Internal synchronisation between two processes
  - know bounds MIN, MAX on message delay
  - also on clock drift, execution rate
- Assume One sends message to Two with time t
  - Two can set its clock to t + (MAX+MIN)/2 (estimate of time taken to send message)
  - then the skew is at most (MAX-MIN)/2
  - why not t + MIN or t + MAX?
    - maximum skew is larger, could be MAX-MIN

Cristian's algorithm



Time Server with UTC receiver gives accurate current time

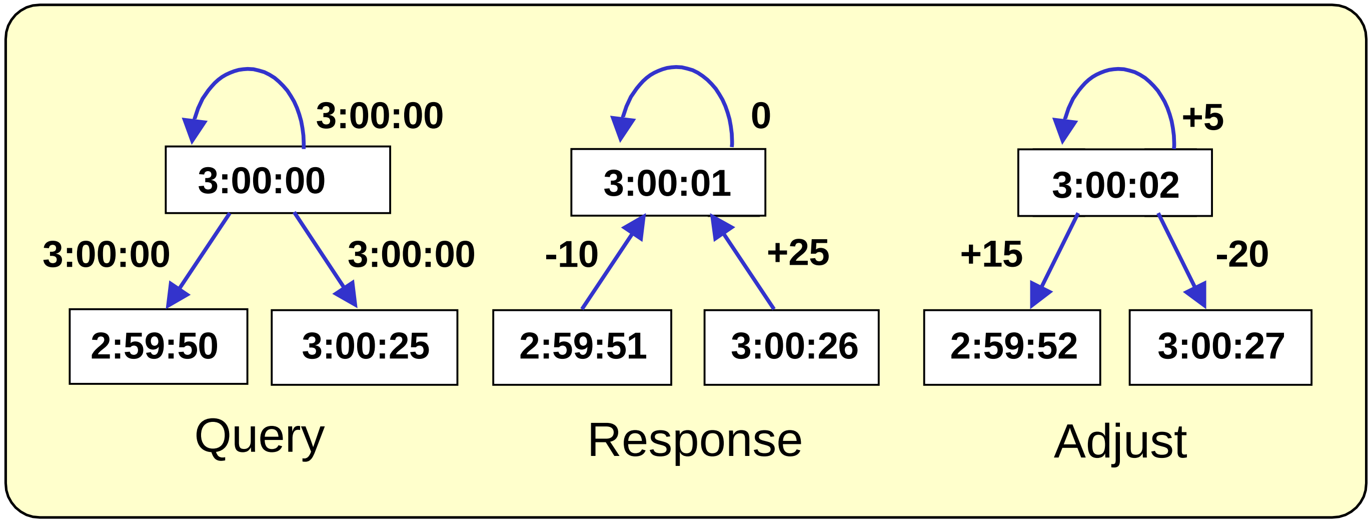
- Estimate message propagation time by $p=(T_1-T_0-h)/2$ (=half of round-trip of request-reply)
- Set clock to UTC+p
- Make multiple requests, at spaced out intervals, measure T_1-T_0
  - but discard any that are over a threshold (could be congestion)
  - or take minimum values as the most accurate

Cristian's algorithm

- Probabilistic behaviour
  - achieves synchronisation only if round-trip short compared to required accuracy
  - high accuracy only for message transmission time close to minimum
- Problems
  - single point of failure and bottleneck
  - could multicast to a group of servers, each with UTC
  - an impostor or faulty server can wreak havoc
    - use authentication
    - agreement protocol for $N > 3f$ clocks, f number of faulty clocks

The Berkeley algorithm

- Choose master co-ordinator which periodically polls slaves
- Master estimates slaves' local time based on round-trip
- Calculates average time of all, ignoring readings with exceptionally large propagation delay or clocks out of synch
- Sends message to each slave indicating clock adjustment



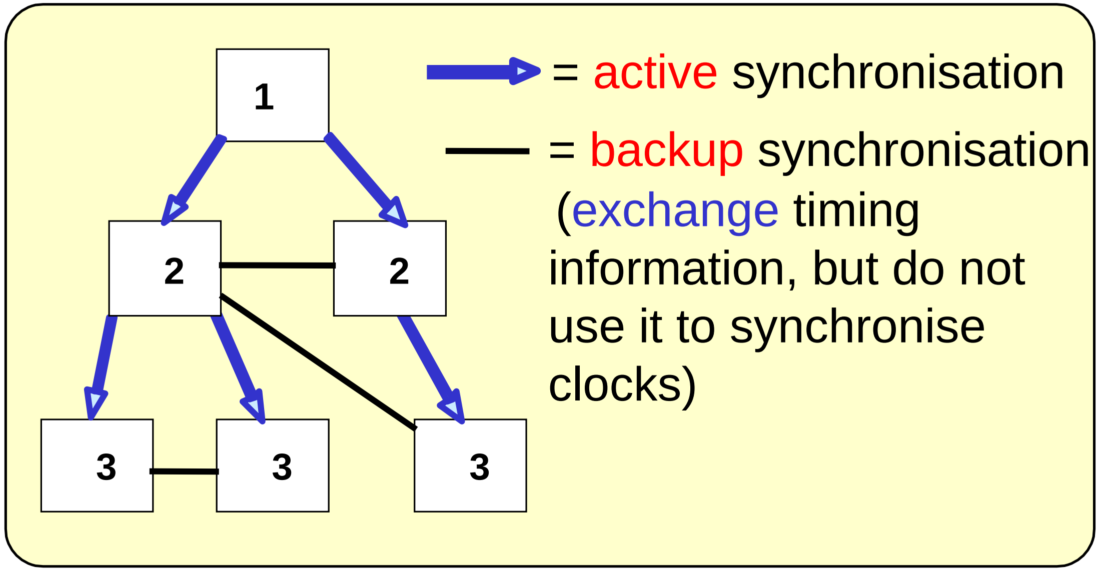
Synchronisation feasible to within 20-25 msec for 15 computers, with drift rate of 2×10^{-5} and max round trip propagation time of 10 msec.

The Berkeley algorithm

- Accuracy
  - depends on the round-trip time
- Fault-tolerant average:
  - eliminates readings of faulty clocks - probabilistically
  - average over the subset of clocks that differ by up to a specified amount
- What if master fails?
  - elect another leader

Network Time Protocol (NTP)

- Multiple time servers across the Internet
- Primary servers: directly connected to UTC receivers
- Secondary servers: synchronise with primaries
- Tertiary servers: synchronise with secondary, etc
- Scales up to large numbers of servers and clients



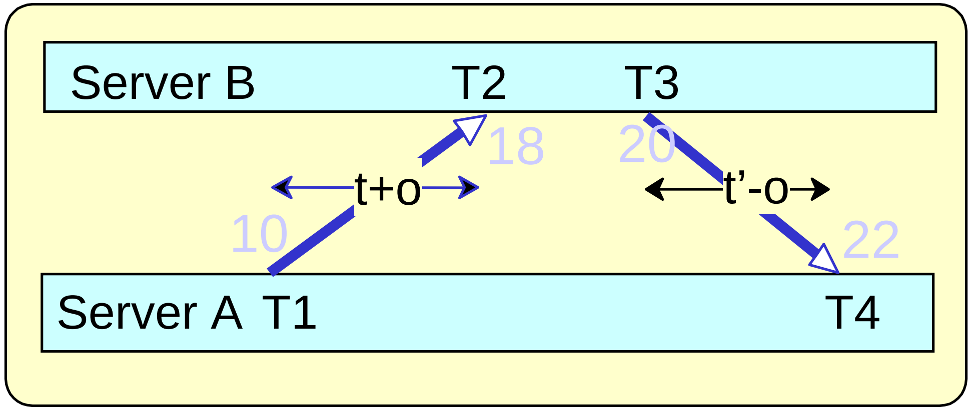
Copes with failures of servers – e.g. if primary's UTC source fails it becomes a secondary, or if a secondary cannot reach a primary it finds another one.

Authentication used to check that time comes from trusted sources

NTP Synchronisation Modes

- Multicast
  - one or more servers periodically multicast to other servers on high speed LAN
  - they set clocks assuming small delay
- Procedure Call Mode
  - similar to Cristian's algorithm: client requests time from a few other servers
  - used for higher accuracy or where no multicast
- Symmetric protocol
  - used by master servers on LANs and layers closest to primaries
  - highest accuracy, based on pairwise synchronisation

NTP Symmetric Protocol



- t = transmission delay (e.g. 5ms)
- o = clock offset of B relative to A (e.g. 3ms)
- Record local times T1 = 10, T2 = 18, T3 = 20, T4 = 22

  Let a = T2-T1= t + o, b = T4-T3 = t' - o, and assume t ≈ t'

  Round trip delay = t + t' = a + b = (T2-T1)+(T4-T3) = 10

  Calculate estimate of clock offset o = (a-b)/2 = 3

NTP Symmetric Protocol

- T4 = current message receive time determined at receiver
- Every message contains
  - T3 = current message send time
  - T2 = previous receive message receive time
  - T1 = previous receive message send time
- Data filtering (obtain average values of clock offset from values of o corresponding to minimum t)
- Peer selection (exchange messages with several peers favouring those closer to primaries)
- How good is it? 20-30 primaries and 2000 secondaries can synchronise to within 30 ms

Logical time

- For many purposes it is sufficient to agree on the same time (e.g. internal consistency) which need not be UTC time
- Can deduce causal event ordering

  $a \rightarrow b$ (a occurs before b)
- Logical time denotes causal relationships
- but the $\rightarrow$ relationship may not reflect real causality, only accidental

Event ordering

Define $a \rightarrow b$ (a occurs before b) if

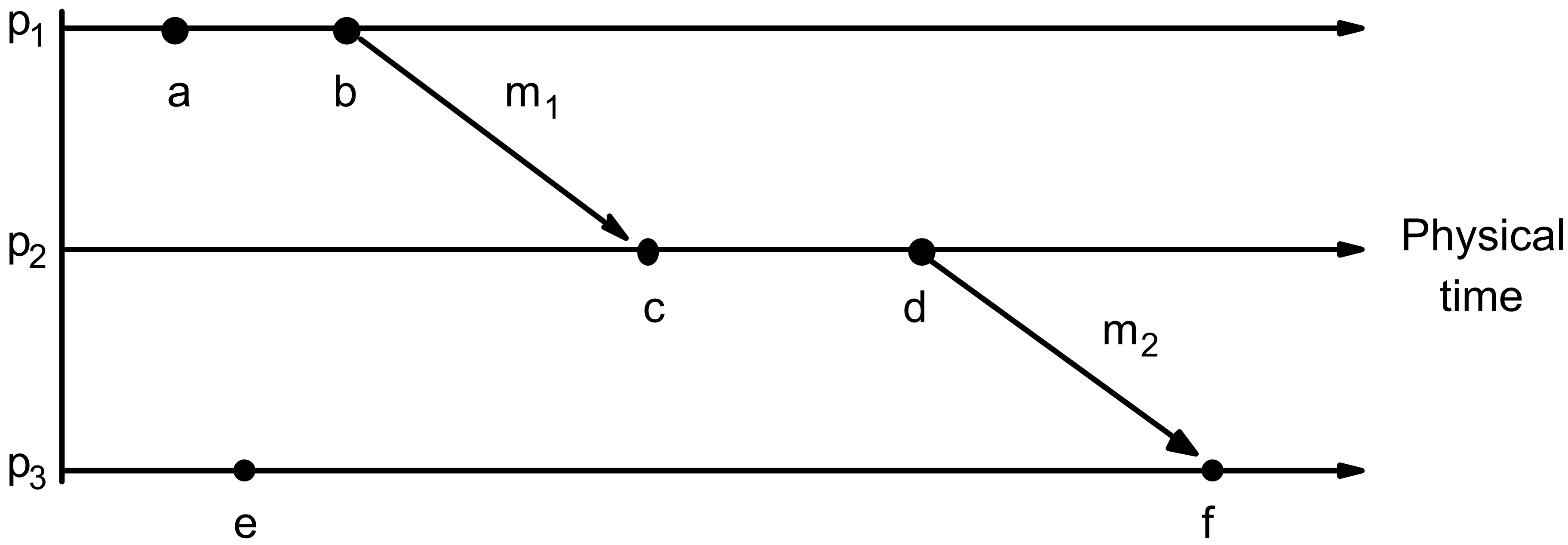
- a and b are events in the same process and a occurs before b, or
- a is the event of message sent from process A and B is the event of message receipt by process B

If $a \rightarrow b$ and $b \rightarrow c$ then $a \rightarrow c$.

$\rightarrow$ is partial order.

For events such that neither $a \rightarrow b$ nor $b \rightarrow a$ we say a, b are concurrent, denoted $a \parallel b$.

Example of causal ordering



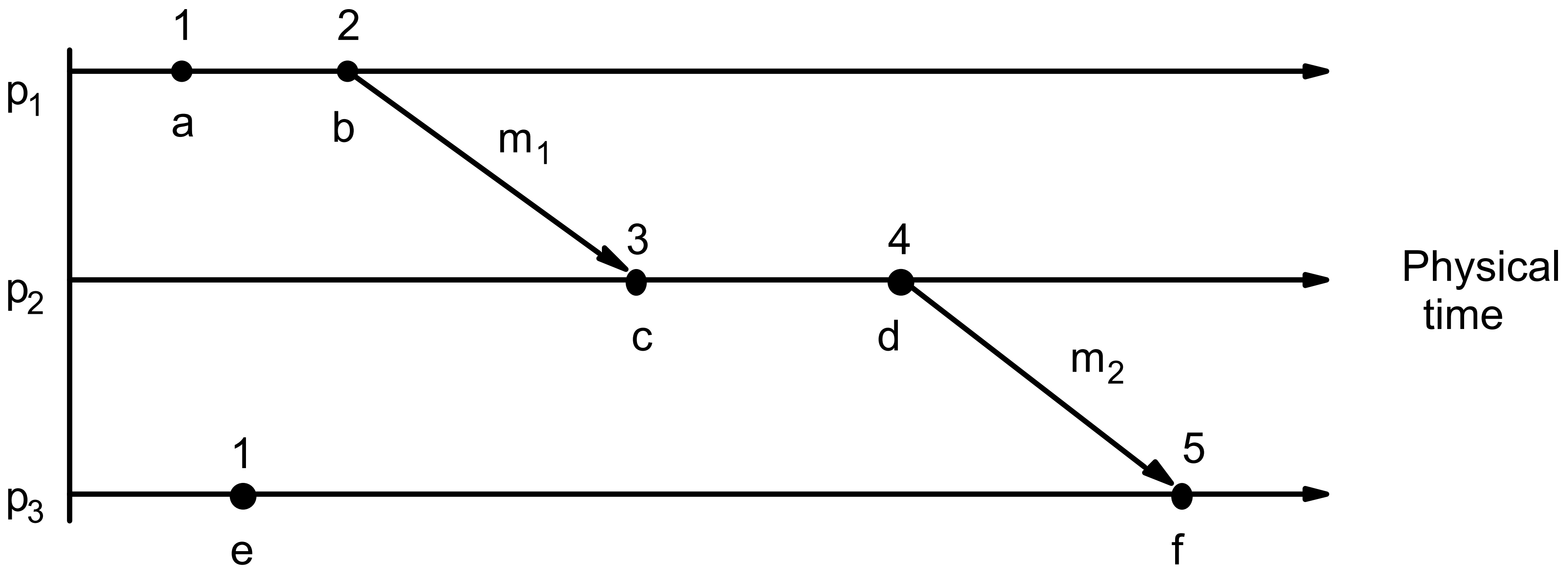
- a $\rightarrow$ b, c $\rightarrow$ d
- b $\rightarrow$ c, d $\rightarrow$ f
- a || e

Logical clocks [Lamport]

- Logical clock = monotonically increasing software counter (not real time!)
  - one for each process P, used for timestamping
- How it works
  - L_P incremented before assigning a timestamp to an event
  - when P sends message m, P timestamps it with current value t of L_P (after incrementing it), piggybacking t with m
  - on receiving message (m,t), Q sets its own clock L_Q to maximum of L_Q and t, then increments L_Q before timestamping the message receive event
- Note $a \rightarrow b$ implies $T(a) < T(b)$

What about converse?

Totally ordered logical clocks

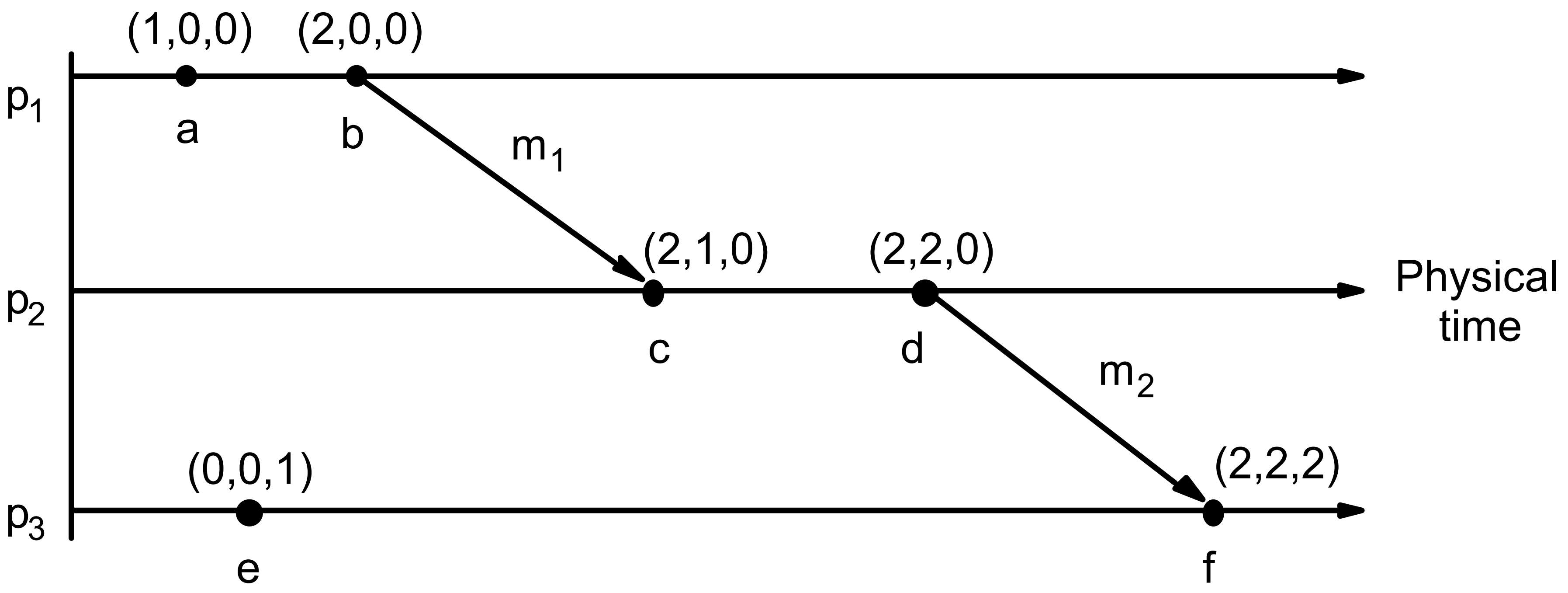


- Problem: T(a) = T(e), and yet a, e distinct.
- Create total order by taking account of process ids.
- Then (T(a),pid) < (T(b),qid) iff T(a) < T(b) or T(a)=T(b) and pid < qid.

Vector clocks

- Totally ordered logical clocks
  - arbitrary event order, depends on order of process ids
  - i.e. (T(a),pid) < (T(b),qid) does not imply a $\rightarrow$ b, see a, e
- Vector clocks
  - array of N logical clocks in each process, if N processes
  - vector timestamps piggybacked on the messages
  - rules for incrementing similar to Lamport's, except
    - processes own component in array modified
    - componentwise maximum and comparison
- Problems
  - storage requirements

Vector timestamps



- VT(b) < VT(c), hence b $\rightarrow$ c
- neither VT(b) < VT(e), nor VT(b) < VT(e), hence b || e

Summary

- Local clocks
  - drift!
  - but needed for timestamping
- Synchronisation algorithms
  - must handle variable message delays
- Clock compensation estimate average delays
  - adjust clocks
  - can deal with faulty clocks
- Logical clocks
  - sufficient for causal ordering