Chasing the Weakest Failure Detector for k-Set Agreement in Message-Passing Systems
Achour Mostefaoui, Michel Raynal, Julien Stainer

To cite this version:

HAL Id: hal-01151291
https://hal.archives-ouvertes.fr/hal-01151291
Submitted on 12 May 2015

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L’archive ouverte pluridisciplinaire HAL, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d’enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.
Chasing the Weakest Failure Detector for $k$-Set Agreement in Message-passing Systems

Achour Mostefaoui  
Université de Nantes, France  
achour.mostefaoui@univ-nantes.fr

Michel Raynal, Julien Stainer  
Université de Rennes 1, France  
{raynal|jstainer}@irisa.fr

Abstract—This paper continues our quest for the weakest failure detector which allows the $k$-set agreement problem to be solved in asynchronous message-passing systems prone to process failures. It has two main contributions which will be instrumental to complete this quest.

The first contribution is a new failure detector (denoted $\Pi\Sigma_{x,y}$) that has several noteworthy properties. (a) It is stronger than $\Sigma_y$, which has been shown to be necessary. (b) It is equivalent to the pair $\langle \Sigma, \Omega \rangle$ when $x = y = 1$ (optimal to solve consensus). (c) It is equivalent to the pair $\langle \Sigma_{x-1}, \Omega_{y-1} \rangle$ when $x = y = n - 1$ (optimal for $(n-1)$-set agreement). (d) It is strictly weaker than the pair $\langle \Sigma_x, \Omega_y \rangle$ (which has been investigated in previous works). (e) It is operational: the paper presents a $\Pi\Sigma_{x,y}$-based algorithm that solves $k$-set agreement for $k \geq xy$ (intuitively, $x$ refers to the maximum number of isolated groups of processes and $y$ to the number of leaders in each of these groups).

The second contribution of the paper is a proof that, for $1 < k < n - 1$, the eventual leaders failure detector $\Omega_k$ (which eventually provides each process with the same set of $k$ process identities, this set including at least one correct process) is not necessary to solve $k$-set agreement problem.

Index Terms—Asynchronous distributed system, Eventual leader, Failure detector, Fault tolerance, Quorum.

I. INTRODUCTION

a) The $k$-set agreement problem: This problem is a natural generalization of the consensus problem. It is a coordination problem (also called decision problem) introduced by S. Chaudhuri [10] to explore the relation linking the number of process failures and the minimal number of values that processes are allowed to decide. This problem can be defined as follows [10]. Each process proposes a value and every non-faulty process has to decide a value (termination), in such a way that a decided value is a proposed value (validity) and no more than $k$ different values are decided (agreement). The problem parameter $k$ defines the coordination degree: $k = 1$ corresponds to its most constrained instance (consensus) while $k = n - 1$ corresponds to its weakest non-trivial instance (called set agreement).

Let $t$ be the model parameter that defines the upper bound on the number of processes that may crash in a run, $0 \leq t < n$. If $t < k$, $k$-set agreement can be trivially solved in both synchronous and asynchronous systems: $k$ predetermined processes broadcast (write in the shared memory) the values they propose and a process decides the first proposed value it receives (reads from the shared memory). Hence, the interesting setting is when $t \geq k$, i.e., when the number of values that can be decided is smaller or equal to the maximal number of processes that may crash in a run.

Round-based algorithms that solve the $k$-set agreement problem for $k \leq t < n$ in crash-prone synchronous message-passing systems are presented in [2], [18]. These algorithms are optimal in the sense that the processes decide in at most $\left\lceil \frac{t}{k} \right\rceil + 1$ rounds which has been shown to be a lower bound on the number of rounds for a process to decide. For asynchronous systems where the processes communicate by reading/writing a shared memory or sending/receiving messages, the situation is different, namely, when $t \geq k$, the $k$-set agreement problem has no solution [6], [16], [25].

b) Failure detectors: Let us observe that in an asynchronous system where the only means for processes to communicate is a read/write shared memory or send/receive message-passing network, no process is able to know if another process has crashed or is only very slow. The concept of a failure detector originates from this simple observation. A failure detector is a device (distributed oracle) that enriches a distributed system by providing alive processes with information on failed processes [8]. Several classes of failure detectors can be defined according to the type of information on failures they provide to processes.

Given a system model $\mathcal{M}$ (e.g., asynchronous read/write shared memory system model or asynchronous send/receive message-passing system model) a failure detector $A$ is stronger than a failure detector $B$ with respect to $\mathcal{M}$ (denoted $A \preceq \mathcal{M} B$ or $B \succeq \mathcal{M} A$) if there is an algorithm (called reduction) that builds $B$ in $\mathcal{M}$ enriched with $A$ (we then also say that $B$ is weaker than $A$). If $A$ is stronger than $B$ and $B$ is stronger than $A$, then $A$ and $B$ are equivalent with respect to $\mathcal{M}$ (denoted $A \simeq \mathcal{M} B$). If $A \preceq \mathcal{M} B$ and $B \not\preceq \mathcal{M} A$ then $A$ is strictly stronger than $B$ -equivalently $B$ is strictly weaker than $A$ (denoted $A \succ \mathcal{M} B$ or $B \prec \mathcal{M} A$). If $A \not\preceq \mathcal{M} B$ and $B \not\preceq \mathcal{M} A$ (denoted $A \not\simeq \mathcal{M} B$), $A$ and $B$ cannot be compared in $\mathcal{M}$.

Failure detectors, to circumvent the “$t \geq k$” impossibility result associated with the $k$-set agreement problem in asynchronous systems, have been investigated since 2000 [19]. (Random oracles to solve the $k$-set agreement problem have also been investigated [20].) The question of the weakest failure detector to solve the $k$-set agreement problem ($k > 1$) has been stated first in [24]. A failure detector $A$ is the weakest failure detector that allows a problem $P$ to be solved in a model $\mathcal{M}$ if any failure detector $B$ that allows $P$ to be solved.
c) The weakest failure detector for $k$-set agreement in shared memory systems where $t = n - 1$: The eventual leader failure detector $\Omega$ introduced in [9] is the weakest failure detector that allows consensus (i.e., 1-set agreement) to be solved in shared memory systems where any number of processes may crash [17]. $\Omega$ ensures that there is an unknown but finite time after which all the processes have the same non-faulty leader (before that time, there is an anarchy period during which each process can have an arbitrarily changing faulty or non-faulty leader). At the other end of the spectrum ($k = n - 1$), the failure detector $\Omega_{n-1}$ (anti-omega) has been introduced in [26] where it is shown to be the weakest failure detector that allows $(n - 1)$-set agreement to be solved in these systems.

A simple generalization of $\Omega$ and $\Omega_{n-1}$ denoted $\Omega_k$, $1 \leq k \leq n - 1$, ($\Omega_1$ is $\Omega$) has been introduced in [23] where it is conjectured to be the weakest failure detector class for solving $k$-set agreement in asynchronous read/write shared memory systems. This conjecture has been proved in [14]. A failure detector of the class $\Omega_k$ provides each process with a (possibly always changing) set of $k$ processes such that, after some unknown but finite time, all the sets that are output have in common the same non-faulty process. The optimality of $\Omega_k$ to solve $k$-set agreement in shared memory systems seems to be related to the fact that this problem is equivalent to the $k$-simultaneous consensus problem [1] in which each process executes $k$ independent consensus instances (to which it proposes the same input value) and is required to terminate in one of them. As indicated in [26], this problem has been instrumental in determining the weakest failure detector for wait-free solving the $(n - 1)$-set agreement problem in asynchronous shared memory systems.

d) The cases $k = 1$ and $k = n - 1$ in message-passing systems where $t = n - 1$: When $k = 1$, as already indicated $k$-set agreement boils down to consensus, and it is known that the failure detector denoted $\Omega$ is the weakest to solve consensus in asynchronous message-passing systems where $t < n/2$ [9]. This lower bound result is extended to any value of $t$ in [12] where the failure detector $\Sigma$ is introduced and is shown that $\Sigma \times \Omega$ is the weakest failure detector to solve consensus in message-passing systems when $t < n$. This means that $\Sigma$ is the minimal additional power (as far as information on failures is concerned) required to overcome the barrier $t < n/2$ and attain $t \leq n - 1$. Actually the power provided by $\Sigma$ is the minimal one required to implement a shared register in a message-passing system [4], [12]. $\Sigma$ provides each process with a quorum (set of process identities) such that the values of any two quorums (each taken at any time) intersect, and there is a finite time after which any quorum includes only correct processes. Fundamentally, $\Sigma$ prevents partitioning. A failure detector $\Sigma \times \Omega$ outputs a pair of values, one for $\Sigma$ and one for $\Omega$.

The Loneliness failure detector (denoted $\mathcal{L}$) has been proposed in [13] where it is proved that it is the weakest failure detector for solving $(n - 1)$-set agreement in the asynchronous message-passing model with $t = n - 1$. Such a failure detector provides each process $p$ with a boolean (that $p$ can only read) such that the boolean of at least one process remains always false and, if all but one process crash, the boolean of the remaining process becomes and remains true forever. Let us notice that the weakest failure detector for $(n - 1)$-set agreement is not the same in the read/write shared memory model (where it is $\Omega_{n-1}$) and the send/receive message-passing model (where it is $\mathcal{L}$).

e) The quest for the weakest failure detector for $k$-set agreement in message-passing systems: This quest seems to be one of the most difficult research topics in the theory of fault-tolerant distributed computing. Since a few years, several new failure detectors have been proposed for solving $k$-set agreement in asynchronous message passing systems prone to any number of crashes, but so far finding the weakest still remains a challenge.

The interested reader will find in [21] a study on relations linking some of these failure detectors. Here we only present the failure detector $\Sigma_x$ introduced in [5] because it is central to the paper. $\Sigma_x$ generalizes the quorum failure detector class $\Sigma$ introduced in [12] ($\Sigma_1$ is $\Sigma$). This failure detector provides each process with a set (quorum) such that at least two quorums do intersect in any set of $x + 1$ quorums (whose values are taken at any times). Moreover, there is a finite (but unknown) time after which the quorum of any process includes only non-faulty processes. Two main results are proved in [5]: (a) as far as information on failures is concerned, $\Sigma_k$ is a necessary requirement to solve $k$-set agreement; (b) $\Sigma_{n-1}$ is sufficient to solve $(n - 1)$-set agreement. Interestingly, a $\Sigma_x$-based algorithm is presented in [7] that solves $k$-set agreement for $k \geq n - \left\lceil \frac{n-1}{x+1} \right\rceil$.

f) Contributions of the paper: This paper is a new step in the quest for the weakest failure detector for $k$-set agreement in message-passing systems. It has two main contributions.

- The first contribution is the definition and the investigation of a new failure detector class denoted $\Pi \Sigma_{x,y}$.
  
  - Intuitively $\Pi \Sigma_{x,1}$ (1) prevents the system from partitioning into more than $k$ independent subsets and (2) guarantees that the processes of at least one of these subsets agree on a common leader. $\Pi \Sigma_{x,y}$ can be seen as $y$ independent instances of $\Pi \Sigma_{x,1}$ in which item (2) is guaranteed in only one of these instances.

  - Let $\text{AMP}$ denote the asynchronous message-passing system model where up to $n - 1$ process may crash. The properties of $\Pi \Sigma_{x,y}$ are the following: (a) $\Pi \Sigma_{1,y} \preceq \text{AMP} \left( \Sigma_1, \mathcal{P}_y \right)$; (b) $\Pi \Sigma_{x,n-1} \preceq \text{AMP} \left( \Sigma_x \right)$; (c) $\Pi \Sigma_{x,y} \preceq \text{AMP} \left( \Sigma_x, \mathcal{P}_y \right)$ for $1 \leq x, y \leq n$ and $\Pi \Sigma_{x,y} \preceq \text{AMP} \left( \Sigma_x, \mathcal{P}_y \right)$ for $1 < y < x < n$. It follows from (a) and (b) that $\Pi \Sigma_{1,1}$ and $\Pi \Sigma_{n-1,n-1}$ are the weakest failure detectors to solve $k$-set agreement for $k = 1$ and $k = n - 1$, respectively.

  For $1 \leq k \leq n - 1$, we have the following.

  An algorithm based on the pair of failure detectors $\langle \Sigma_x, \mathcal{P}_y \rangle$ is presented in [7] that solves $k$-set agree-
computability power than $\Omega$ is not sufficient to prove our theorem since it is necessary to solve the set agreement problem in the asynchronous message-passing model enriched with a failure detector. The previous asynchronous crash-prone message-passing system model is denoted $\text{AMP}[\emptyset]$. $\text{AMP}$ stands for “Asynchronous Message-Passing”; $\emptyset$ means this is the “base” system (not enriched with a failure detector).

### B. The $k$-Set agreement problem

As already indicated in the Introduction, the $k$-set agreement problem has been introduced by Soma Chaudhuri [10]. It generalizes the consensus problem (that corresponds to $k = 1$). It is defined as follows. Each process proposes a value and has to decide a value in such a way that the following properties are satisfied:

- Termination. Every correct process decides a value.
- Validity. A decided value is one of the proposed values.
- Agreement. At most $k$ different values are decided.

### III. EXISTING FAMILIES OF FAILURE DETECTORS

This section presents failure detectors that have been proposed in the quest of the weakest failure detector for $k$-set agreement. The system model $\text{AMP}[\emptyset]$ enriched with a failure detector $A$ is denoted $\text{AMP}[A]$.

A failure detector provides each alive process with a read-only local variable. Let $xxx_i$ be such a variable of process $p_i$. Let $xxx_i^\tau$ denote the value of $xxx_i$ at time $\tau$.

#### A. The $\Omega_k$ and $\Omega_k^j$ families

The eventuality failure detectors of the families $\Omega_k$ and $\Omega_k^j$ provide each process $p_i$ with a local variable denoted $\text{leaders}_i^\tau$. They originate from $\Omega$ [9] ($\Omega_1 \equiv \Omega_k \equiv \Omega$). $\Omega_k^j$ is a straightforward generalization of $\Omega_k$ (introduced in [26]). $\Omega_k^j$ has been shown to be the weakest failure detector to solve $k$-set agreement in asynchronous shared memory systems with any number of process crashes in [14]. Let us consider the following properties on the sets $\text{leaders}_i^\tau$:

- **Validity.** $\forall i, \forall \tau: \text{leaders}_i^\tau$ is a set of $k$ process identities.
- **Strong eventual leadership.** $\exists L \subseteq \tau, \forall \tau' \geq \tau: (L \cap C \neq \emptyset) \land (\forall \tau' \geq \tau, \forall i \in C: \text{leaders}_i^\tau = L)$.
- **Weak eventual leadership.** $\exists \ell \in C, \forall \tau' \geq \tau, \forall i \in C: \ell \in \text{leaders}_i^\tau$.

Validity combined with strong eventual leadership states that, after some unknown but finite time, all correct processes have the same set of $k$ leaders and at least one of them is a correct process. Validity combined with weak eventual leadership requires only that the correct processes eventually share a common correct leader.
l) The $\Omega_k$ family: This family (introduced in [22]) includes the failure detectors that satisfy the validity and strong eventual leadership properties.

m) The $\Pi_k$ family: This family (introduced in [23]) includes the failure detectors that satisfy the validity and weak eventual leadership properties.

B. The $\Sigma_k$ and $\Pi_k$ families

n) The $\Sigma_k$ family: As noticed in the subsection, the generalized quorum failure detector $\Sigma_k$ (introduced in [5]) is a generalization of the quorum failure detector $\Sigma$ introduced in [12] where it is shown to be the weakest failure detector to implement a register in $AMP[\emptyset]$. $\Sigma_k$ provides each process $p_i$ with a set $qr_i$ (called quorum) that satisfies the following properties (after a process $p_i$ has crashed, we have $qr_i = P$ by definition). The self-inclusion property (which does not appear in [5]) is considered here because it allows for a simpler formulation of algorithms.

- Self-inclusion. $\forall i \in P, \forall \tau: i \in qr_i \tau^r$. 
- Quorum liveness. $\exists \tau: \forall i \in C, \forall \tau' \geq \tau: qr_i \tau' \subseteq C$. 
- Quorum intersection. $\exists \tau_1, \ldots, \tau_{k+1} \in P, \forall i: j \in C \exists i, j: (i \neq j) \land (qr_{i \tau_1} \cap qr_{j \tau_{k+1}} \neq \emptyset)$. 

It is shown in [5] that $\Sigma_k$ is necessary when one wants to solve k-set agreement in $AMP[\emptyset]$.

o) The $\Pi_k$ family: The failure detector $\Pi_k$ (introduced in [5]) is an extension of $\Sigma_k$ to which it adds the following property.

- Eventual leadership. $\exists LD, \tau: ((LD) = k) \land (\forall \tau' \geq \tau, \forall i \in C: qr_i \tau' \subseteq LD \neq \emptyset)$. 

It is shown in [5] that $\Pi_k$ and the pair $\langle \Sigma_k, \Omega_k \rangle$ are equivalent, i.e., $\Pi_k$ can be built in $AMP[\Sigma_k, \Omega_k]$ and $\langle \Sigma_k, \Omega_k \rangle$ can be built in $AMP[\Pi_k]$. It is also shown in [5] that $\Pi_{n-1}$ and $L$ are equivalent. If follows from these observations that $\Pi_1$ and $\Pi_{n-1}$ are the weakest failure detectors for $k = 1$ and $k = n - 1$. Unfortunately, as shown in [3], [7], $\Pi_k$ does not allow to solve k-set agreement for $1 < k < n - 1$.

IV. THE FAMILY OF FAILURE DETECTORS $\Pi\Sigma_{x,y}$

A. Definition

The definition of $\Pi\Sigma_{x,y}$ is incremental, first is defined $\Pi\Sigma_x$ and then $\Pi\Sigma_{x,y}$.

p) The failure detector $\Pi\Sigma_x$: A failure detector $\Pi\Sigma_x$ provides each process $p_i$ with a set $qr_i$ and a variable $leader_i$ which define the current quorum and the current leader of $p_i$. It is defined by the following properties.

- Self-inclusion. $\forall i \in P, \forall \tau: i \in qr_i \tau^r$. 
- Quorum liveness. $\exists \tau: \forall i \in C, \forall \tau' \geq \tau: qr_i \tau' \subseteq C$. 
- Quorum intersection. $\exists \tau_1, \ldots, \tau_{k+1} \in P, \forall i: j \in C \exists i, j: (i \neq j) \land (qr_{i \tau_1} \cap qr_{j \tau_{k+1}} \neq \emptyset)$. 
- Eventual leadership. $\exists \tau: \forall i \in C: (\exists \tau: \tau \geq \tau_i \tau' \cap qr_i \tau' \neq \emptyset) \Rightarrow (\exists i: \forall \tau' \geq \tau: leader_i \tau' = \ell)$. 

The self-inclusion, liveness and intersection properties are the properties that define $\Sigma_x$: after some time the quorum of any correct process contains only correct processes (liveness) and any set of $x + 1$ quorums contains two intersecting quorums (intersection). Hence, $\Pi\Sigma_x \supseteq \Sigma_x$.

Eventual partial leadership states that there is a correct process $p_i$ such that, for any correct process $p_j$ whose quorum $qr_j$ intersects infinitely often its quorum $qr_i$ (left part of the implication), then eventually $p_i$ is forever the leader of $p_j$ (right part of the implication).

q) The failure detector $\Pi\Sigma_{x,y}$: $\Pi\Sigma_x$ is $\Pi\Sigma_{x,1}$. More generally, $\Pi\Sigma_{x,y}$ provides each process $p_i$ with an array $FD_i[1..y]$ such that for each each $j \in \{1, \ldots, y\}$, $FD_i[j]$ is a pair containing a quorum $FD_i[j], leader$ and a process index $FD_i[j], leader$. Let $FD[j]$ denote the corresponding distributed object (ie, $FD[j]$ on $p_i$ is represented by $FD_i[j]$). The failure detector $\Pi\Sigma_{x,y}$ consists of an array $FD[1..y]$ that satisfies the following properties:

- Vector safety. $\forall j \in \{1..y\}: FD[j], qr$ satisfies the liveness and intersection properties of $\Pi\Sigma_x$.
- Vector liveness. $\exists j \in \{1..y\}: FD[j], leader$ satisfies the eventual partial leadership property of $\Pi\Sigma_x$ related to $FD[j], qr$ for the same $j$.

B. $\Pi\Sigma_{x,y}$ vs $\langle \Sigma_x, \Omega_y \rangle$

A failure detector $\langle \Sigma_x, \Omega_y \rangle$ provides each process $p_i$ with two independent read-only local variables: $qr_i$ that satisfies the properties defined by $\Sigma_x$, and $leader_i$ that satisfies the properties defined by $\Omega_y$.

Lemma 1: Let $1 \leq x, y \leq n - 1$. $\Pi\Sigma_{x,y} \cong_{AMP} \langle \Sigma_x, \Omega_y \rangle$.

Algorithm 1 From $\langle \Sigma_x, \Omega_y \rangle$ to $\Pi\Sigma_{x,y}$ (code for $p_i$)

(01) repeat forever rel_broadcast leader(leader), end repeat.

(02) when leader(id) is delivered:

(03) for each $j \neq id$ do suspnardb[j] ← suspnardb[j] + 1 end for;

(04) let $j_1, j_2, \ldots, j_n$ be a permutation of $\{1, \ldots, n\}$ such that $\langle suspnardb[j_1], j_1 \rangle < \langle suspnardb[j_2], j_2 \rangle < \ldots \ldots < \langle suspnardb[j_n], j_n \rangle$;

(05) for each $x \in \{1, \ldots, y\}$ do $FD[x].leader ← j_x$ end for.

Theorem 1: Let $1 \leq y \leq n - 1$. $\Pi\Sigma_{1,y} \cong_{AMP} \langle \Sigma_1, \Omega_y \rangle$.

Proof: Taking $x = 1$ in Lemma 1 we have $\Pi\Sigma_{1,y} \cong_{AMP} \langle \Sigma_1, \Omega_y \rangle$. Hence, we have only to show that $\langle \Sigma_1, \Omega_y \rangle \cong_{AMP} \Pi\Sigma_{1,y}$.

Let $qr_1$ of $\Sigma_1$ be the output of $FD[1], qr$. Hence, the quorums $qr_i$ inherit the liveness and intersection properties of $FD[1], qr$ that trivially satisfy the properties defining $\Sigma_1$.

Let $leader_i$ be any subset of size $y$ that contains $\cup_{1 \leq i \leq y} \{FD[i], leader\}$. Due to the vector liveness property of $\Pi\Sigma_{1,y}$, there is an entry $j$ such that $FD[j]$ satisfies the eventual partial leadership (Observation O1). Moreover, as $x = 1$, any pair of quorums output by $FD[j]$ do intersect (Observation O2). It follows from O1 and O2 that there is a correct process $p_j$ such that, for each correct process $p_i$, there is a time after which the predicate $FD[i], leader = \ell$ remains forever true. Consequently, there is a finite time after which the predicate $\ell \in leader_i$ remains forever true at any correct process $p_i$, from which follows the weak eventual leadership property of $\Omega_y$. □
Theorem 2: Let $1 \leq x \leq n-1$. $\Pi \Sigma_{x,n-1} \simeq_{\text{AMP}} \Sigma_x$.

Proof: Taking $y = n - 1$ in Lemma 1 we have $\Pi \Sigma_{x,n-1} \simeq_{\text{AMP}} (\Sigma_x, \Omega_{n-1})$. Hence, we have only to show that $(\Sigma_x, \Omega_{n-1}) \simeq_{\text{AMP}} \Pi \Sigma_{x,n-1}$.

It is shown in [5] (Corollary 2 in [5]) that $\Sigma_x \simeq_{\text{AMP}} \Sigma_{x+1} \simeq_{\text{AMP}} \cdots \simeq_{\text{AMP}} \Sigma_{n-1} \simeq_{\text{AMP}} \Omega_{n-1}$. Moreover, it follows directly from their definitions that $\Omega_{n-1} \simeq_{\text{AMP}} \Pi \Sigma_{x,n-1}$. It follows that $\Sigma_x \simeq_{\text{AMP}} (\Sigma_x, \Omega_{n-1})$ which completes the proof of the theorem. \(\square\)

Lemma 2: Let $1 \leq y < n$. $\Pi \Sigma_{y+1,1} \not\simeq_{\text{AMP}} (\Sigma_x, \Omega_{y})$.

Theorem 3: Let $1 < y < x < n$. $\Pi \Sigma_{x,y} \nsubseteq_{\text{AMP}} (\Sigma_x, \Omega_{y})$.

Proof: $\Pi \Sigma_{x,y} \nsubseteq_{\text{AMP}} (\Sigma_x, \Omega_{y})$ follows from Lemma 1. Hence, we have to show that $\Pi \Sigma_{x,y} \not\simeq_{\text{AMP}} (\Sigma_x, \Omega_{y})$. Let us first observe that $\Pi \Sigma_{y+1,1} \simeq_{\text{AMP}} \Pi \Sigma_{y+1,y}$. This is easily obtained by providing each $FD[j]$ of the array $FD[1..y]$ with the outputs supplied by $\Pi \Sigma_{y+1,1}$. On another side, (as shown in [5]) $\Sigma_x$ is strictly stronger than $z < x$ for $1 \leq z < n - 1$ and, consequently, $\Pi \Sigma_{y+1,1} \simeq_{\text{AMP}} \Pi \Sigma_{y+1,y}$ for $y < x$. It follows from Lemma 2 (i.e., $\Pi \Sigma_{y+1,1} \not\simeq_{\text{AMP}} (\Sigma_x, \Omega_{y})$) that, as $\Pi \Sigma_{x,y} \simeq_{\text{AMP}} \Pi \Sigma_{y+1,1}$, we have $\Pi \Sigma_{x,y} \not\simeq_{\text{AMP}} (\Sigma_x, \Omega_{y})$ which proves the theorem. \(\square\)

Remark: A main difference between $\Pi \Sigma_{x,y}$ and $(\Sigma_x, \Omega_{y})$ lies in the fact that the eventual correct leader elected by $\Pi \Sigma_{x,y}$ to be the same for all correct processes, while $\Pi \Sigma_{x,y}$ requires only that the correct processes of a subset (dynamically defined by one of the $x$ failures) agree on a common leader. Hence, the scope of the leadership provided by $\Pi \Sigma_{x,y}$ is not required to be the whole system but only a subset of it.

V. A BASIC BUILDING BLOCK: THE ALPHA$_x$ ABSTRACTION

A. Definition of ALPHA$_x$

This paper presents an algorithm that solves the $k$-set agreement problem in $\text{AMP} [\Pi \Sigma_{x,y}]$. This algorithm uses an abstraction called ALPHA$_x$ and has been introduced in [15] to capture the safety property of consensus and generalized in [24] to capture the safety property of $k$-set agreement in crash-prone systems. [15], [24] give corresponding implementations in read/write shared memory systems and send/receive message-passing systems.

Let $\bot$ be a default value that cannot be proposed by processes. ALPHA$_x$ is an object initialized to $\bot$ that may store up to $x$ different values proposed by processes. It is an abstraction (object) that provides processes with a single operation denoted $\text{propose}(r,v)$ (where $r$ is a round number and $v$ a proposed value) that returns a value to the invoking process. The round number plays the role of the global time that allows identifying the propose() invocations. It is assumed that distinct processes use different round numbers and successive invocations by the same process use increasing sequence numbers. ALPHA$_x$ is a kind of abortable object in the sense that propose() invocations are allowed to return the default value $\bot$ (i.e., abort) in specific concurrency-related circumstances (as defined from the obligation property, see below). More precisely, the ALPHA$_x$ objects used in this paper are defined by the following specification in which the obligation property takes explicitly into account the fact that we are interested into an ALPHA$_x$ object that will be implemented on top of $\text{AMP}[\Sigma_x]$ (which is a strictly stronger underlying model than $\text{AMP}[0]$).

- Termination. Any invocation of propose() by a correct process terminates.
- Validity. If propose$(r,v)$ returns $v' \neq \bot$, then propose$(r',v')$ has been invoked with $r' \leq r$.
- Quasi-agreement. At most $k$ different non-$\bot$ values can be returned by propose() invocations.
- Obligation. $p_i$ being a correct process let $Q(r,\tau) = \{i \in C | \forall \pi_i, \tau_i \geq \tau : qr_\pi^\tau_i \cap qr_\rho^\tau_i = \emptyset\}$. If, after time $\tau$, (a) only $p_i$ and processes of $Q(r,\tau)$ invoke propose() and (b) $p_i$ invokes propose() infinitely often, then at least one invocation issued by $p_i$ returns $\bot$.

Differently from the obligation property stated in [7], [15], [24] the previous obligation property is $\Sigma_x$-aware which allows for a weaker property (the ALPHA$_x$ object used in [7] is implemented on top of $\text{AMP}[\Sigma_x]$ but its specification is not $\Sigma_x$-aware). More precisely, our obligation property allows concurrent invocations of propose() to return $\bot$ values as soon as the quorums of the invoking processes do not intersect during these invocations.

B. THE ALPHA$_x$ OBJECT USED BY BOUZID AND TRAVERS [7]

This section presents an implementation of an ALPHA$_x$ object on top of $\text{AMP}[\Sigma_x]$. This implementation is obtained from a modification of the algorithm proposed in [7] which is first described.

1. The obligation property used in [7]: The ALPHA$_x$ object used in [7] has the same specification as the one defined in this paper (which is close to the one defined in [15], [24]) but for the obligation property which (similarly to [15]) is defined as follows.

- Obligation. Let $I = \text{propose}(r,-)$ be a terminating invocation. If every invocation $I' = \text{propose}(r',-)\tau$ that starts before $I$ returns is such that $r' < r$, then $I$ returns a $\bot$ value.

It is easy to see that this specification is not $\Sigma_x$-aware. In presence of concurrent invocations, it directs at most one process to decide a $\bot$ value, namely, the one with the highest round number. The current outputs of $\Sigma_x$ are irrelevant in this statement.

2. Principles: establish a priority on values: Each process $p_i$ manages a local variable $est_i$ (initialized to $\bot$) that represents its current estimate $v$ of the value it will decide and a pair $(lre_i, pos_i)$ that defines the priority associated with $v$ from $p_i$’s point of view (the aim is to decide values with the highest priority); $lre_i = r$ means that $r$ is the highest round seen by $p_i$ and $pos_i = r \in [1...2^\ell]$ is the position of $v$ in round $r$. The pairs $(r, \rho)$ are used to establish a priority on proposed values. The function $g(\rho, \delta) = 2^\delta(\rho - 1) + 1$
(where δ is a difference between two round numbers) is used to compute the priority of a value in the following rounds. More precisely, let \((r, p)\) and \((r', p')\) (such that \(r \leq r'\)) be the pairs associated with the values \(v\) and \(v'\), respectively. Value \(v\) has lower priority than value \(v'\) at round \(r'\) if \(g(p, r') < p'\) or \((g(p, r') = p') \land (v < v')\).

Our description of Bouzid-Travers’s algorithm (algorithm 2) is schematic. The reader will refer to [7] for more detailed presentation and a proof. The implementation of the operation \(\text{propose}()\) is made up of two sequential phases: a read phase followed by write phase.

**Algorithm 2** \(\text{Alpha}_x\) in AMP[\(\Sigma_x\)]: Bouzid-Travers’s implementation [7]

```
\begin{algorithm}
\textbf{init} \(\text{lre}_i \leftarrow 0; \text{est}_i \leftarrow \bot; \text{pos}_i \leftarrow 0\).

\textbf{operation} \(\text{propose}(r, v)\):
\begin{enumerate}
\item broadcast \(\text{REQ}_R(r)\);
\item repeat \(Q_i \leftarrow q_i\).
\item until \((\forall j \in Q_i) : \text{_RSP}_R(\text{lre}_j, \text{pos}_j, \text{est}_j)\) received from \(p_j\).
\end{enumerate}

\textbf{end repeat};

\textbf{end if};

\textbf{end if};

\end{algorithm}
```

Then, when it has received a response from each process in its current quorum \(q_{ri}\), as supplied by \(\Sigma_x\) (lines 02-04), \(p_i\) returns \(\bot\) if it has received an answer indicating that another process has started a round higher than \(\text{lre}_i\) (lines 05-06). Otherwise, \(\text{lre}_i = r\) is the greatest round number known by \(p_i\). In that case, \(p_i\) updates \(\text{pos}_i\) to the greatest position associated with round \(r\) it has seen and adopts the corresponding value \(v\) as its current estimate \(\text{est}_i\) (lines 07 and 08). Moreover, if \(v = \bot\), \(p_i\) adopts \(v_i\) into \(\text{est}_i\), namely, the value it proposes to the \(\text{Alpha}_x\) object (line 09).

**v) Succinct description of the algorithm: the write phase:**

Process \(p_i\) enters then a loop that it will exit either by returning \(\bot\) (line 19) or its current estimate value (line 23). The maximum number of times that this loop can be executed depends on the round number \(r\) and the current position value \(\text{pos}_i\) (line 10). The part of the loop body defined by lines 12-21 is the same as lines 01-08. The difference is that, instead of obtaining information on the current state, \(p_i\) cooperate with the processes of its current quorum \(q_{ri}\) in order to try to increase the priority of its current \(\text{est}_i\). Hence instead of a read-request, \(p_i\) broadcasts write-request messages.

Each time a process \(p_j\) receives such a message that carries a triplet \((rd, pos, val)\) it updates its current state in order this local state contains the value with the highest priority (and the associated control data). Operationally, if \(rd \geq \text{lre}_j\), \(p_j\) first updates \(\text{pos}_j\) and \(\text{lre}_j\) (line 26) exactly as it did at line 24 when it received a read-request message. Then, according to the value of \(\text{pos}_j\) and \(\text{pos}\) (lines 27-30), \(p_j\) updates \(\text{est}_j\) and \(\text{pos}_j\), if \(\text{pos}_j > \text{pos}\), or updates only \(\text{est}_j\) if \(\text{pos}_j = \text{pos}\). In all cases, \(p_j\) sends back a response carrying its local state to the process that sent the write-request.

As already indicated, a proof that this algorithm implements an \(\text{Alpha}_x\) object that satisfies the round-based obligation property stated at the beginning of this section is given in [7].

C. An implementation of \(\text{Alpha}_x\) as defined in this paper

Algorithm 3 describes an implementation of the \(\Sigma_x\)-aware specification of \(\text{Alpha}_x\) defined in Section V-A. This algorithm is an appropriate improvement of Algorithm 2.

To make the presentation easier, the line numbers are the same in both algorithms. The lines that are new or modified are prefixed by the letter N. These modifications concern message filtering. This filtering is used to prevent a process \(p_i\) from sending read or write-requests to the processes \(p_j\) such that \(p_i\) does not need information from \(p_j\) to complete its current invocation of \(\text{propose}()\). Hence, such a process \(p_j\) cannot direct \(p_i\) to return \(\bot\) while it could return a non-\(\bot\) value (and additionally the values not sent by \(p_i\) cannot force other processes to return \(\bot\)).

**w) Modification of the read phase:** A process \(p_j\) records in \(r_{\text{req-set}}\) the set of processes to which it has already sent a \(\text{REQ}_R(r)\) message (lines N01 and N02-2) and sends read-request messages \(\text{REQ}_R(r)\) only to the processes \(p_j\) that belong to its quorum \(q_{ri}\) (line N02-1).
Then, when it stops waiting for response messages, it considers only the responses sent by the processes of its last quorum plus its own response (lines N05-1 and N05-2).

x) Modification of the write phase: The message exchange pattern of that phase is modified similarly to what has been done for the read phase (lines N12, N14-1, N14-2, N17-1 and N17-2).

Algorithm 3 Alpha_x in AMP[Σ_k] as defined in Section V

```
init lreq_i ← 0; est_i ← ⊥; pos_i ← 0.
operation propose((r, v_i)): (N01) r_req_set_i ← 0; (N02-1) send REQ_R(r) to each p_j, j ∈ Q_t \ r_req_set_i; (N02-2) r_req_set_i ← r_req_set_i ∪ Q_t;
until (\exists j ∈ Q_t : (r, (est_j, pos_j, est_j))) received from p_j) (N04) end repeat;
(N05-1) let rcv_i = \{ (lreq_i, pos_i, est_j) \}; (N05-2) rsp_R(r, (lreq_i, pos_i, est_j)) received from Q_t ; (N06) if (\exists lreq_i : (lreq_i, −, −) ∈ rcv_i : lreq_i > lreq_i) then return(⊥) end if;
(N07) pos_i ← max{pos_i | (r, pos_i, v_i) ∈ rcv_i}; (N08) est_i ← max{lreq_i | (r, pos_i, v_i) ∈ rcv_i}; (N09) if (est_i = ⊥) then est_i ← v_i end if;
(N10) while(pos_i < 2^k) do
(N11) pos_i ← pos_i + 1; pst_i ← pos_i; \// this line is executed atomically
(N12) w_req_set_i ← 0;
(N13) repeat Q_t, q_i;
(N14-1) send REQ_W((q_i, pos_i, est_j)) to each p_j, j ∈ Q_t \ w_req_set_i;
(N14-2) w_req_set_i ← w_req_set_i ∪ Q_t;
(N14-3) until (\exists j ∈ Q_t : (q_i, (est_j, pos_j, est_j))) received from p_j;
(N15) rsp_W((q_i, pos_i, est_j)) received from p_j;
(N16) end repeat;
(N17-1) rcv_i ← \{(lreq_i, pos_i, est_j) \}; (N17-2) rsp_W((q_i, pos_i, est_j)) received from Q_t ; (N19) if (\exists lreq_i : (lreq_i, −, −) ∈ rcv_i : lreq_i > r) then return(⊥) end if;
(N20) pos_i ← max{pos_i | (r, pos_i, v_i) ∈ rcv_i}; (N21) est_i ← max{lreq_i | (r, pos_i, v_i) ∈ rcv_i};
(N22) end while;
(N23) return(est_i).
when REQ_R(rd) received from p_j:
(N24) if rd > lreq_i then pos_i ← g(pos_i, rd − lreq_i); lreq_i ← rd end if;
(N25) send rsp_R((rd, (lreq_i, pos_i, est_j))) to p_j.
when REQ_W(rd, pos, est) received from p_j:
(N26) if rd ≥ lreq_i then pos_i ← g(pos_i, rd − lreq_i); lreq_i ← rd
(N27) case pos_i > pos_j then est_i ← est_j; pos_i ← pos_j
(N28) pos_i = pos_j then est_i ← max{v_i, est_j}
(N29) pos_i < pos_j then nop
(N30) end case
(N31) end if;
(N32) send rsp_W((rd, (lreq_i, pos_i, est_j))) to p_j.
```

Theorem 4: Algorithm 3 implements an Alpha_x object as defined in Section V-A.

VI. SOLVING k-SET AGREEMENT IN AMP[ΠΣ_{xy}]

This section presents a simple algorithm that implements k-set agreement in AMP[ΠΣ_{xy}] for k ≥ xy. It is similar to the one presented in [7]: it uses a base algorithm (similar to the one introduced in [15]) that solves x-set agreement in AMP[ΠΣ_{x}] and then assuming k ≥ xy (as in [1], [7]) it uses y instances of this base to solve k-set agreement in AMP[ΠΣ_{xy}].

y) x-Set agreement in AMP[ΠΣ_{x}] : Algorithm 4 solves x-set agreement in AMP[ΠΣ_{x}]. A process p_i invokes ks_propose_{x} (v_i) where v_i is the value it proposes. It decides a value d when it executes the statement return (d) which terminates its invocation. The local variable r_i is the local round number (as it is easy to see, each process uses increasing round numbers and no two distinct processes use the same round numbers). A process loops until it decides. If during a loop iteration p_i is such that leader_i = i (leader_i is one of the two local outputs provided by ΠΣ_{x}), p_i invokes the Alpha_x object to try to deposit its value v_i into it (the success depends on the concurrency and quorums pattern). If a non-⊥ value is returned by this invocation, p_i broadcasts it (with the reliable broadcast operation). A process decides as soon as it is delivered a decision() message.

Algorithm 4 x-set agreement in AMP[ΠΣ_{x}] (p_i’s code)

```
operation ks_propose_{x} (v_i):
(01) dec_i ← ⊥; r_i ← i;
(02) while (dec_i = ⊥) do
(03) if (leader_i = i) then Alpha_x.propose(r_i, v_i); r_i ← r_i + 1 end if
(04) end while;
(05) rel_broadcast decision(dec_i);
when decision(d) is delivered: return(d).
```

Theorem 5: Algorithm 4 solves the x-set agreement in AMP[ΠΣ_{x}].

Proof: Validity and agreement properties. Let us first observe that, due to the test of line 02, the default value ⊥ cannot be decided. The fact that a decided value is a proposed value follows then from the validity of the underlying Alpha_x object. Similarly, the fact that at most k non-⊥ values are decided follows directly from the quasi-agreement property of the underlying Alpha_x object.

Termination property. It follows from the reliable broadcast operation that, at soon as a process decides (invokes return()) each correct process eventually delivers the same decision(d) message and decides (if not yet done). The proof is by contradiction: assuming that no process decides, we show that at least one correct process executes rel_broadcast() (and consequently, all correct processes decide).

Let p_{ℓ} be a correct process that appears in the definition of the eventual partial leadership property of ΠΣ_{x}. It follows from the definition of p_{ℓ} that we eventually have forever leader_{x} = ℓ.

Let R_τ be the set of the identities of the processes p_j (with j ≠ ℓ) such that we have leader_j = j infinitely often. It follows from the contrapositive of the eventual partial leadership property of ΠΣ_{x} that there is a time τ_{R_τ} such that \forall j ∈ R_τ, \forall τ_1, τ_2 ≥ τ_{R_τ}: qr_τ^1 ∩ qr_τ^2 = ∅, from which we conclude that R_τ ⊆ Q(ℓ, τ_{R_τ}) (this is the set defined in the obligation property of Alpha_x).

Let us notice that, due to test of line 03, there is a
finite time $\tau_n$ after which the only processes that invoke $\text{Alpha}_x$\_propose() are the processes in $R_\ell \cup \{l\}$. Moreover (as by the contradiction assumption no process decides) it follows that, after $\tau_n$, $p_l$ invokes $\text{Alpha}_x$\_propose() infinitely often. Let $\tau_n$ be a time greater than $\max(\tau_{R_\ell}, \tau_n)$ from which we have $R_\ell \subseteq Q(\ell, t_{R_\ell}) \subseteq Q(\ell, \tau_n)$.

As after $\tau_n$ (a) only processes in $R_\ell \cup \{\ell\}$ invoke $\text{Alpha}_x$\_propose(), (b) $p_l$ invokes $\text{Alpha}_x$\_propose() infinitely often and (c) $R_\ell \subseteq Q(\ell, \tau_n)$, we conclude from the obligation property of $\text{Alpha}_x$ that at least one invocation of $p_\ell$ returns a value $d \neq \perp$ and consequently executes $\text{rel}_\text{broadcast decision}(d)$. This contradicts the fact that no process decides and concludes the proof of the theorem.

$\square$ Theorem 5

z) $k$-Set agreement in $\mathcal{AMP}[\Pi\Sigma_{x,y}]$: As in [1], [7], a simple $k$-set algorithm can be obtained by launching concurrently $y$ instances of Algorithm 4, the $j$th one relying on the component $\text{FD}[j]$ of the failure detector $\mathcal{AMP}[\Pi\Sigma_{x,y}]$. A process decides the value returned by the first of the $y$ instances that locally terminates. As there are $y$ instances of Algorithm 4 and at most $x$ values can be decided in each of them, it follows that at most $xy$ different values can be decided. Moreover, as at least one $\text{FD}[j]$ is a $\Pi\Sigma_{x,y}$ failure detector, it follows that the correct processes decide (if not done before) in at least one of the $y$ instances of Algorithm 4. Let us observe that, in such a “worst” case where the processes decide in the same instance, at most $x$ values are decided.

VII. $\Omega_k$ IS NOT NECESSARY FOR $k$-SET AGREEMENT WHEN

1. $k < n - 1$

Lemma 3: Let $1 < k < n - 1$. $\Omega_k$ cannot be built in $\mathcal{AMP}[\Pi\Sigma_{k,1}]$.

Theorem 6: Let $1 < k < n - 1$. $\Omega_k$ is not necessary for solving $k$-set agreement in $\mathcal{AMP}[\emptyset]$. Let $X(k)$ denote the (still unknown) weakest failure detector such that $k$-set agreement can be solved in $\mathcal{AMP}[X(k)]$. The following corollary shows that, when $1 < k < n - 1$, $\Omega_k$ is neither necessary nor sufficient for solving the $k$-set agreement problem.

Corollary 1: Let $1 < k < n - 1$. $\Omega_k \notin \mathcal{AMP} X(k)$.

VIII. CONCLUSION

As indicated in the abstract, this paper is a new step in the quest for discovering the weakest failure detector for $k$-set agreement in asynchronous message-passing systems prone to any number of process failures. It has presented a new failure detector denoted $\Pi\Sigma_{x,y}$ which enjoys many noteworthy features and an associated algorithm that solves $k$-set agreement for $k \geq xy$. It has also shown that the weakest failure detector (that still remains to be discovered) and $\Omega_k$ (a well-studied failure detector) cannot be compared.

More generally, an important issue that remains to be solved lies in capturing the “weakest” type of shared memory that has to be emulated for solving $k$-set agreement in asynchronous message-passing systems.

REFERENCES


