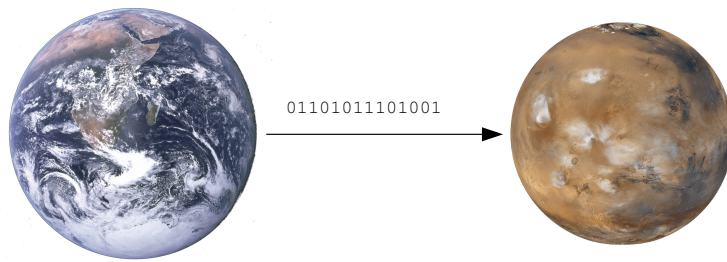


MARS Manual

Multiversion Asynchronous Replicated Storage



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Version 0.9 (incomplete)

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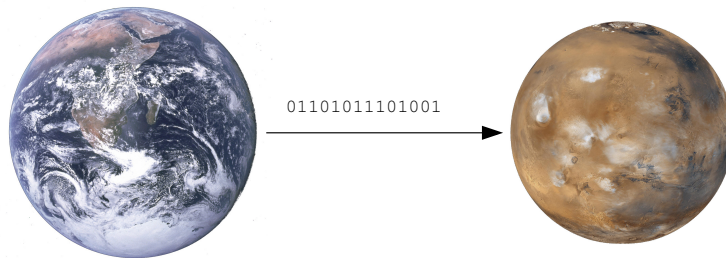
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Abstract

MARS Light is a block-level storage replication system for long distances / flaky networks under GPL. It runs as a Linux kernel module. The sysadmin interface is similar to DRBD¹, but its internal engine is completely different from DRBD: it works with **transaction logging**, similar to some database systems.

Therefore, MARS Light can provide stronger **consistency guarantees**. Even in case of network bottlenecks / problems / failures, the secondaries may become outdated (reflect an elder state), but never become inconsistent. In contrast to DRBD, MARS Light preserves the **order of write operations** even when the network is flaky (**Anytime Consistency**).

The current version of MARS Light works **asynchronously**. Therefore, application performance is completely decoupled from any network problems. Future versions are planned to also support synchronous or near-synchronous modes.



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1. Use Cases for MARS vs DRBD

DRBD has a long history of successfully providing HA features to many users of Linux. With the advent of MARS, many people are wondering what the difference is. They ask for recommendations. In which use cases should DRBD be recommended, and in which other cases is MARS the better choice?

There exist *some* cases where DRBD is better than MARS. 1&1 has a long history of experiences with DRBD where it works very fine, in particular coupling Linux devices rack-to-rack via crossover cables. DRBD is just *constructed* for that use case (RAID-1 over network).

On the other hand, there exist other cases where DRBD did not work as expected, leading to incidents and other operational problems. We analyzed them for those use cases, and found that they could only be resolved by fundamental changes in the overall architecture of DRBD. Therefore, we started the development of MARS.

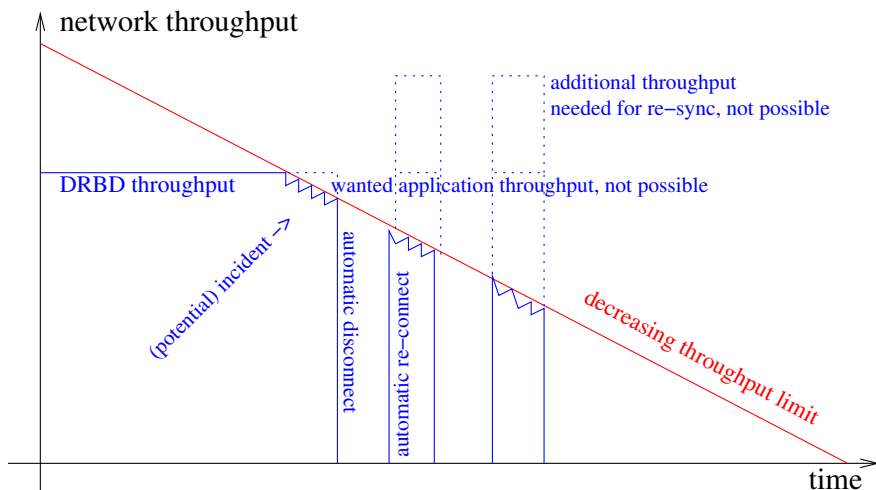
MARS and DRBD simply have **different application areas**.

In the following, we will discuss the pros and cons of each system in particular situations and contexts, and we shed some light at their conceptual and operational differences.

1.1. Network Bottlenecks

1.1.1. Behaviour of DRBD

In order to describe the most important problem we found when DRBD was used to couple whole datacenters (each encompassing thousands of servers) over metro distances, we strip down that complicated real-life scenario to a simplified laboratory scenario in order to demonstrate the effect with minimal means. The following picture illustrates an effect which is not only observable in practice, but is also reproducible by the MARS test suite¹:



The simplified scenario is the following:

1. DRBD is loaded with a low to medium, but constant rate of write operations for the sake of simplicity of the scenario.
2. The network has some throughput bottleneck, depicted as a red line. For the sake of simplicity, we just linearly decrease it over time, starting from full throughput, down to zero. The decrease is very slowly over time (some minutes, or even hours).

¹The effect has been demonstrated with DRBD version 8.3.13. By construction, it is independent from any of the DRBD series 8.3.x, 8.4.x, or 9.0.x.

What will happen in this scenario?

As long as the actual DRBD write throughput is lower than the network bandwidth (left part of the horizontal blue line), DRBD works as expected.

Once the maximum network throughput (red line) starts to fall short of the required application throughput (first blue dotted line), we get into trouble. By its very nature, DRBD works **synchronously**. Therefore, it *must* transfer all your application writes through the bottleneck, but now it is impossible² due to the bottleneck. As a consequence, the application running on top of DRBD will see increasingly higher IO latencies and/or stalls / hangs. We found practical cases (at least with former versions of DRBD) where IO latencies exceeded practical monitoring limits such as 5 s by far, up to the range of *minutes*. As an experienced sysadmin, you know what happens next: your application will run into an incident, and your customers will be dissatisfied.

In order to deal with such situations, DRBD has lots of tuning parameters. In particular, the `timeout` parameter and/or the `ping-timeout` parameter will determine when DRBD will give up in such a situation and simply drop the network connection as an emergency measure. Dropping the network connection is roughly equivalent to an automatic `disconnect`, followed by an automatic re-connect attempt after `connect-int` seconds. During the dropped connection, the incident will appear as being resolved, but at some hidden cost³.

What happens next in our scenario? During the `disconnect`, DRBD will record all positions of writes in its bitmap and/or in its activity log. As soon as the automatic re-connect succeeds after `connect-int` seconds, DRBD has to do a partial re-sync of those blocks which were marked dirty in the meantime. This leads to an *additional* bandwidth demand⁴ as indicated by the upper dotted blue box.

Of course, there is *absolutely no chance* to get the increased amount of data through our bottleneck, since not even the ordinary application load (lower dotted lines) could be transferred.

Therefore, you run at a **very high risk** that the re-sync cannot finish before the next `timeout` / `ping-timeout` cycle will drop the network connection again.

What will be the final result when that risk becomes true? Simply, your secondary site will be in state **inconsistent**. This means, you have lost your redundancy. In our scenario, there is no chance at all to become consistent again, because the network bottleneck declines more and more, slowly. It is simply *hopeless*, by construction.

In case you lose your primary site now, you are lost at all.

Some people may argue that the probability for a similar scenario were low. We don't agree on such an argumentation. Not only because it really happens in practice, and it may even last some days until problems are fixed. In case of **rolling disasters**, the network is very likely to become flaky and/or overloaded shortly before the final damage. Even in other cases, you can easily end up with inconsistent secondaries. It occurs not only in the lab, but also in practice if you operate some hundreds or even thousands of DRBD instances.

The point is that you can produce an ill behaviour *systematically* just by overloading the network a bit for some sufficient duration.

²This is independent from the DRBD protocols A through C, because it just depends on an information-theoretic argument independently from any protocol. We have a fundamental conflict between network capabilities and application demands here, which cannot be circumvented due to the **synchronous** nature of DRBD.

³By appropriately tuning various DRBD parameters, such as `timeout` and/or `ping-timeout`, you can keep the impact of the incident below some viable limit. However, the automatic disconnect will then happen earlier and more often in practice. Flaky or overloaded networks may easily lead to an enormous number of automatic disconnects.

⁴DRBD parameters `sync-rate` resp `resync-rate` may be used to tune the height of the additional demand. In addition, the newer parameters `c-plan-ahead`, `c-fill-target`, `c-delay-target`, `c-min-rate`, `c-max-rate` and friends may be used to dynamically adapt to *some* situations where the application throughput *could* fit through the bottleneck. These newer parameters were developed in a cooperation between 1&1 and Linbit, the maker of DRBD.

Please note that lowering / dynamically adapting the resync rates may help in lowering the *probability* of occurrences of the above problems in practical scenarios where the bottleneck would recover to viable limits after some time. However, lowering the rates will also increase the *duration* of re-sync operations accordingly. The *total amount of re-sync data* simply does not decrease when lowering `resync-rate`; it even tends to increase over time when new requests arrive. Therefore, the *expectancy value* of problems caused by *strong* network bottlenecks (i.e. when not even the ordinary application rate is fitting through) is *not* improved by lowering or adapting `resync-rate`, but rather the expectancy value mostly depends on the *relation* between the amount of holdback data versus the amount of application write data, both measured for the duration of some given strong bottleneck.

1. Use Cases for MARS vs DRBD



When coupling whole datacenters via some thousands of DRBD connections, any (short) network loss will almost certainly increase the re-sync network load each time the outage appears to be over. As a consequence, overload may be *provoked* by the re-sync repair attempts. This may easily lead to self-amplifying **throughput storms** in some resonance frequency (similar to self-destruction of a bridge when an army is marching over it in lockstep).

The only way for reliable prevention of loss of secondaries is to start any re-connect *only* in such situations where you can *predict in advance* that the re-sync is *guaranteed* to finish before any network bottleneck / loss will cause an automatic disconnect again. We don't know of any method which can reliably predict the future behaviour of a complex network.



Conclusion: in the presence of network bottlenecks, you run a considerable risk that your DRBD mirrors get destroyed just in that moment when you desperately need them.



Notice that crossover cables usually never show a behaviour like depicted by the red line. Crossover cables are *passive components* which normally⁵ either work, or not. The binary connect / disconnect behaviour of DRBD has no problems to cope with that.



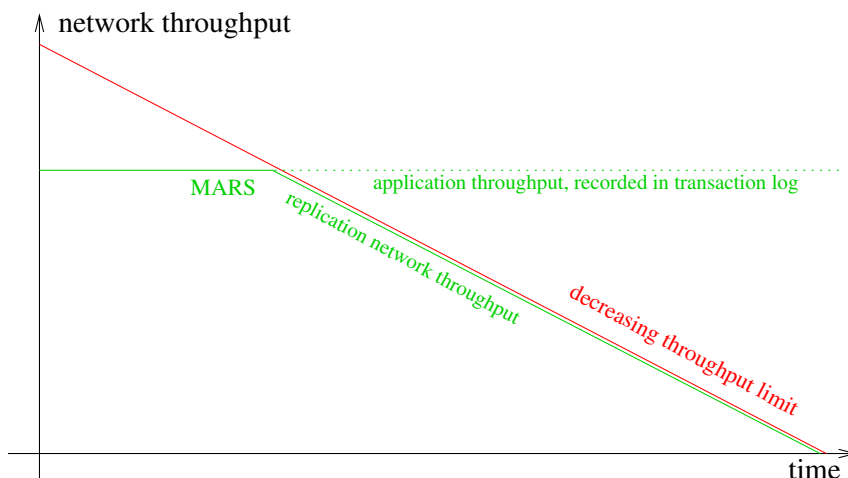
Linbit recommends a **workaround** for the inconsistencies during re-sync: LVM snapshots. We tried it, but found a *performance penalty* which made it prohibitive for our concrete application. A problem seems to be the cost of destroying snapshots. LVM uses by default a BOW strategy (Backup On Write, which is the counterpart of COW = Copy On Write). BOW increases IO latencies during ordinary operation. Retaining snapshots is cheap, but reverting them may be very costly, depending on workload. We didn't fully investigate that effect, and our experience is a few years old. You might come to a different conclusion for a different workload, for newer versions of system software, or for a different strategy if you carefully investigate the field.



DRBD problems usually arise *only* when the network throughput shows some “awkward” analog behaviour, such as overload, or as occasionally produced by various switches / routers / transmitters, or other potential sources of packet loss.

1.1.2. Behaviour of MARS

The behaviour of MARS in the above scenario:



When the network is restrained, an asynchronous system like MARS will continue to serve the user IO requests (dotted green line) without any impact / incident while the actual network

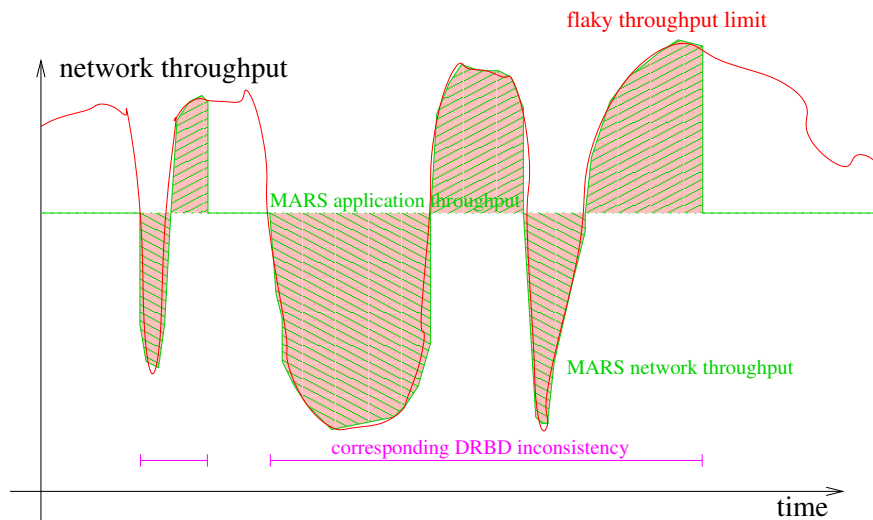
⁵Exceptions might be mechanical jiggling of plugs, or electro-magnetical interferences. We never noticed any of them.

throughput (solid green line) follows the red line. In the meantime, all changes to the block device are recorded at the transaction logfiles.



Here is one point in favour of DRBD: MARS stores its transaction logs on the filesystem `/mars/`. When the network bottleneck is lasting very long (some days or even some weeks), the filesystem will eventually run out of space some day. Section 3.4 discusses countermeasures against that in detail. In contrast to MARS, DRBD allocates its bitmap *statically* at resource creation time. It uses up less space, and you don't have to monitor it for (potential) overflows. The space for transaction logs is the price you have to pay if you want or need anytime consistency, or asynchronous replication in general.

In order to really grasp the *heart* of the difference between synchronous and asynchronous replication, we look at the following modified scenario:



This time, the network throughput (red line) is varying⁶ in some unpredictable way. As before, the application throughput served by MARS is assumed to be constant (dotted green line, often superseded by the solid green line). The actual replication network throughput is depicted by the solid green line.

As you can see, a network dropdown undershooting the application demand has no impact on the application throughput, but only on the replication network throughput. Whenever the network throughput is held back due to the flaky network, it simply catches up as soon as possible by overshooting the application throughput. The amount of lag-behind is visualized as shaded area: downward shading (below the application throughput) means an increase of the lag-behind, while the upwards shaded areas (beyond the application throughput) indicate a decrease of the lag-behind (catch-up). Once the lag-behind has been fully caught up, the network throughput suddenly jumps back to the application throughput (here visible in two cases).



Note that the existence of lag-behind areas is roughly corresponding to DRBD disconnect states, and in turn to DRBD inconsistent states of the secondary as long as the lag-behind has not been fully caught up. The very rough⁷ duration of the corresponding DRBD inconsistency phase is visualized as magenta line at the time scale.

⁶In real life, many long-distance lines or even some heavily used metro lines usually show fluctuations of their network bandwidth by an order of magnitude, or even higher. We have measured them. The overall behaviour can be characterized as “**chaotic**”.

⁷Of course, this visualization is not exact. On one hand, the DRBD inconsistency phase may start later as depicted here, because it only starts *after* the first automatic disconnect, upon the first automatic re-connect. In addition, the amount of resync data may be smaller than the amount of corresponding MARS transaction logfile data, because the DRBD bitmap will coalesce multiple writes to the same block into one single transfer. On the other hand, DRBD will transfer no data at all during its disconnected state, while MARS continues its best. This leads to a prolongation of the DRBD inconsistent phase. Depending on properties of the workload and of the network, the real duration of the inconsistency phase may be both shorter or longer.

1. Use Cases for MARS vs DRBD



MARS utilizes the existing network bandwidth as best as possible in order to pipe through as much data as possible, provided that there exists some data requiring expedition. Conceptually, there exists no better way due to information theoretic limits (besides data compression).



In case of lag-behind, the version of the data replicated to the secondary site corresponds to some time in the past. Since the data is always transferred in the same order as originally submitted at the primary site, the secondary never gets inconsistent. Your mirror always remains usable. Your only potential problem could be the outdated state, corresponding to some state in the past. However, the “as-best-as-possible” approach to the network transfer ensures that your version is always *as up-to-date as possible* even under ill-behaving network bottlenecks. **There is simply no better way to do it.** In presence of network bottlenecks, there exists no better method than prescribed by the information theoretic limit (red line, neglecting data compression).

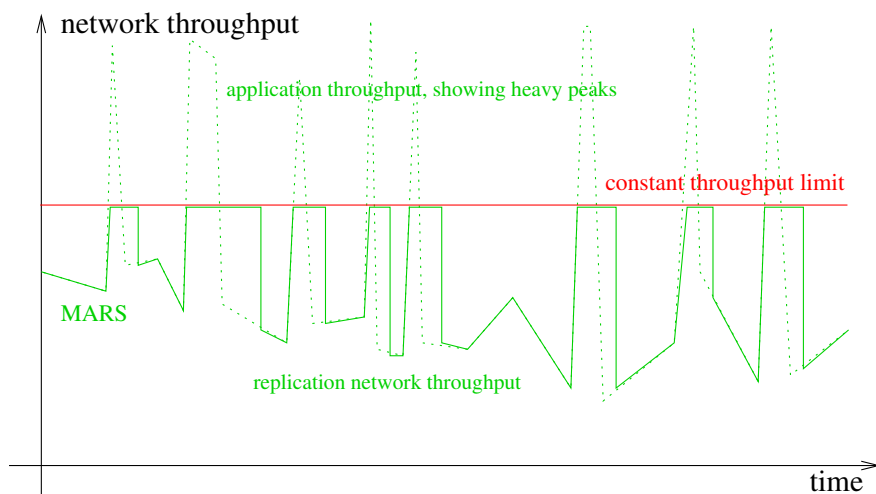


MARS’ property of never sacrificing local data consistency (at the possible cost of actuality) is called **Anytime Consistency**.



Conclusion: you can even use **traffic shaping** on MARS’ TCP connections in order to globally balance your network throughput (of course at the cost of actuality, but without sacrificing local data consistency). If you would try to do the same with DRBD, you could easily provoke a disaster. MARS simply tolerates any network problems, provided that there is enough disk space for transaction logfiles. Even in case of completely filling up your disk with transaction logfiles after some days or weeks, you will not lose local consistency anywhere (see section 3.4).

Finally, here is yet another scenario where MARS can cope with the situation:



This time, the network throughput limit (solid red line) is assumed to be constant. However, the application workload (dotted green line) shows some heavy peaks. We know from our 1&1 datacenters that such an application behaviour is very common.

When the peaks are exceeding the network capabilities for some time, the replication network throughput (solid green line) will be limited for a short time, stay a little bit longer at the limit, and finally drop down again to the normal workload. In other words, you get a flexible buffering behaviour, coping with the peaks.

Similar scenarios (where both the application workload has peaks and the network is flaky to some degree) are rather common. If you would use DRBD there, you were likely to run

into regular application performance problems and/or frequent automatic disconnect cycles, depending on the height and on the duration of the peaks, and on network resources.

1.2. Long Distances / High Latencies

In general and in some theories, latencies are conceptually independent from throughput, at least to some degree. There exist all 4 possible combinations:

1. There exist lines with high latencies but also high throughput. Examples are raw fibre cables at the ground of the Atlantic.
2. High latencies on low-throughput lines is very easy to achieve. If you never saw it, you never ran interactive `vi` over `ssh` in parallel to downloads on your old-fashioned modem line.
3. Low latencies need not be incompatible with high throughput. See Myrinet, InfiniBand or high-speed point-to-point interconnects, such as modern memory busses.
4. Low latency combined with low throughput is also possible: in an ATM system (or another pre-reservation system for bandwidth), just increase the multiplex factor on low-capacity but short lines, which is only possible at the cost of assigned bandwidth.

In the *internet* practice, however, it is very likely that high latencies will also lead to worse throughput, because of the *congestion control algorithms* running all over the world.

We have experimented with extremely large TCP send/receive buffers plus various window sizes and congestion control algorithms over long-distance lines between the USA and Europe. Yes, it is possible to improve the behaviour to some degree. But magic does not happen. Natural laws will always hold. You simply cannot travel faster than the speed of light.

Our experience leads to the following rule of thumb, not formally proven by anything, but just observed in practice:

In general, synchronous data replication (not limited to applications of DRBD) works reliably only over distances < 50 km.

There may be some exceptions, at least when dealing with low-end workstation loads. But when you are responsible for a whole datacenter and/or some centralized storage units, don't waste your time by trying (almost) impossible things. We recommend to use MARS in such use cases.

1.3. Higher Consistency Guarantees vs Actuality

We already saw in section 1.1 that certain types of network bottlenecks can easily (and reproducibly) destroy the consistency of your DRBD secondary, while MARS will preserve local consistency at the cost of actuality (**anytime consistency**).

Some people, often located at database operations, are obtrusively arguing that actuality is such a high good that it must not be sacrificed under any circumstances.

Anyone arguing this way has at least the following choices (list may be incomplete):

1. None of the above use cases for MARS apply. For instance, short distance replication over crossover cables is sufficient (which occurs very often), or the network is reliable enough such that bottlenecks can never occur (e.g. because the total load is extremely low, or conversely the network is extremely overengineered / expensive), or the occurrence of bottlenecks can *provably* be taken into account. In such cases, DRBD is clearly the better solution than MARS, because it provides better actuality than the current version of MARS, and it uses up less disk resources.
2. In the presence of network bottlenecks, people didn't notice and/or didn't understand and/or did under-estimate the risk of accidental invalidation of their DRBD secondaries. They should carefully check that risk. They should convince themselves that the risk is

1. Use Cases for MARS vs DRBD

really bearable. Once they are hit by a systematic chain of events which *reproducibly* provoke the bad effect, it is too late⁸.

3. In the presence of network bottlenecks, people found a solution such that DRBD does not automatically re-connect after the connection has been dropped due to network problems (c.f. `ko-count` parameter). So the risk of inconsistency *appears* to have vanished. In some cases, people did not notice that the risk has *not completely*⁹ vanished, and/or they did not notice that now the actuality produced by DRBD is even drastically worse than that of MARS (in the same situation). It is true that DRBD provides better actuality in **connected** state, but for a full picture the actuality in **disconnected** state should not be neglected¹⁰. So they didn't notice that their argumentation on the importance of actuality may be fundamentally wrong. A possible way to overcome that may be re-reading section 1.1.2 and comparing its outcome with the corresponding outcome of DRBD in the same situation.
4. People are stuck in contradictive requirements because the current version of MARS Light does not yet support synchronous or pseudo-synchronous operation modes. This should be resolved some day.



A common misunderstanding is about the actuality guarantees provided by filesystems. The buffer cache / page cache uses by default a **writeback strategy** for performance reasons. Even modern journalling filesystems will (by default) provide only consistency guarantees, but no strong actuality guarantee. In case of power loss, some transactions may be even *rolled back* in order to restore consistency. According to POSIX¹¹ and other standards, the only *reliable* way to achieve actuality is usage of system calls like `sync()`, `fsync()`, `fdatasync()`, flags like `O_DIRECT`, or similar. For performance reasons, the *vast majority of applications* don't use them at all, or use them only sparingly!



It makes no sense to require strong actuality guarantees from any block layer replication (whether DRBD or future versions of MARS) while higher layers such as filesystems or even applications are already sacrificing them!



In summary, the **anytime consistency** provided by MARS is an argument you should consider, even if you need an extra hard disk for transaction logfiles.

⁸Some people seem to need a bad experience before they get the difference between risk caused by reproducible effects and inverted luck.

⁹Hint: what's the *conceptual* difference between an automatic and a manual re-connect? Yes, you can try to *lower* the risk in some cases by transferring risks to human analysis and human decisions, but did you take into account the possibility of human errors?

¹⁰Hint: a potential hurdle may be the fact that the current format of `/proc/drbd` does neither display the timestamp of the first *relevant* network drop nor the total amount of lag-behind user data (which is *not* the same as the number of dirty bits in the bitmap), while `marsadm view` can display it. So it is difficult to judge the risks. Possibly a chance is inspection of DRBD messages in the `syslog`, but quantification could remain hard.

¹¹The above argumentation also applies to Windows filesystems in analogous way.

2. Quick Start Guide

This chapter is for impatient but experienced sysadmins who already know DRBD. For more complete information, refer to chapter [The Sysadmin Interface `marsadm`](#).

2.1. Preparation: What you Need

Typically, you will use MARS Light at servers in a datacenter for replication of big masses of data.

Typically, you will use MARS Light for replication *between* multiple datacenters, when the distances are greater than ≈ 50 km. Many other solutions, even from commercial storage vendors, will not work reliably over large distances when your network is not *extremely* reliable, or when you try to push huge masses of data from high-performance applications through a network bottleneck. If you ever encountered suchlike problems (or try to avoid them in advance), MARS is for you.

You can use MARS Light both at dedicated storage servers (e.g. for serving Windows clients), or at standalone Linux servers where CPU and storage are not separated.

In order to protect your data from low-level disk failures, you should use a hardware RAID controller with BBU. Software RAID is explicitly *not* recommended, because it generally provides worse performance due to the lack of a hardware BBU (for some benchmark comparisons with/out BBU, see <https://github.com/schoebel/blkreplay/raw/master/doc/blkreplay.pdf>).

Typically, you will need more than one RAID set¹ for big masses of data. Therefore, use of LVM is also recommended² for your data.

MARS' tolerance of networking problems comes with some cost. You will need some extra space for the transaction logfiles of MARS, residing at the `/mars/` filesystem.

The exact space requirements for `/mars/` depend on the *average write rate* of your application, not on the size of your data. We found that only few applications are writing more than 1 TB per day. Most are writing even less than 100 GB per day. Usually, you want to dimension `/mars/` such that you can survive a network loss lasting 3 days / about one weekend. This can be achieved with current technology rather easily: as a simple rule of thumb, just use one **dedicated disk** having a capacity of 4 TB or more. Typically, that will provide you with plenty of headroom even for bigger networking incidents.

Dedicated disks for `/mars/` have another advantage: their mechanical head movement is completely independent from your data head movements. For best performance, attach that dedicated disk to your hardware RAID controller with BBU, building a separate RAID set (even if it consists only of a single disk – notice that the **hardware BBU** is the crucial point).

If you are concerned about reliability, use two disks switched together as a relatively small RAID-1 set. For extremely high performance demands, you may consider (and check) RAID-10.

Since the transaction logfiles are highly sequential in their access pattern, a cheap but high-capacity SATA disk (or nearline-SAS disk) is usually sufficient. At the time of this writing, standard SATA SSDs have shown to be *not* (yet) preferable. Although they offer high random IOPS rate, their sequential throughput is worse, and their long-term stability is questioned by many people at the time of this writing. However, as technology evolves and becomes more mature, this could change in future.

Use `ext4` for `/mars/`. Avoid `ext3`, and don't use `xfs`³ at all.

¹For low-cost storage, RAID-5 is no longer regarded safe for today's typical storage sizes, because the error rate is regarded too high. Therefore, use RAID-6. If you need more than 15 disks in total, create multiple RAID sets (each having at most 15 disks, better about 12 disks) and stripe them via LVM (or via your hardware RAID controller if it supports RAID-60).

²You may also combine MARS with commercial storage boxes connected via Fibrechannel or iSCSI, but we have not yet operational experiences at 1&1 with such setups.

³It seems that the late internal resource allocation strategy of `xfs` (or another currently unknown reason) could be the reason for some resource deadlocks which appear only with `xfs` and only under *extremely* high IO

2.2. Setup Primary and Secondary Cluster Nodes

If you already use DRBD, you may migrate to MARS (or even back from MARS to DRBD) if you use *external*⁴ DRBD metadata (which is not touched by MARS).

2.2.1. Kernel and MARS Module

At the time of this writing, a small pre-patch for the Linux kernel is needed. It is trivial and consists mostly of `EXPORT_SYMBOL()` statements. The pre-patch must be applied to the kernel source tree before building your (custom) kernel. Hopefully, the patch will be integrated upstream some day.

The MARS kernel module can be built in two different ways:

1. inplace in the kernel source tree: `cd block/ && git clone git://github.com/schoebel/mars`
2. as a separate kernel module, only for experienced⁵ sysadmins: see file `Makefile.dist` (tested with Debian; may need some extra work with other distros).

Further / more accurate / latest instructions can be found in `README` and in `INSTALL`. You must not only install the kernel and the `mars.ko` kernel module to all of your cluster nodes, but also the `marsadm` userspace tool.

2.2.2. Setup your Cluster Nodes

For your cluster, you need at least two nodes. In the following, they will be called A and B. In the beginning, A will have the **primary** role, while B will be your initial **secondary**. The roles may change later.

1. You must be `root`.
2. On each of A and B, create the `/mars/` mountpoint.
3. On each node, create an `ext4` filesystem on your separate disk / RAID set (see description in section **Preparation: What you Need**).
4. On each node, mount that filesystem to `/mars/`. It is advisable to add an entry to `/etc/fstab`.
5. On node A, say `marsadm create-cluster`.
This must be done *exactly once*, on exactly one node of your cluster. Never do this twice or on different nodes, because that would create two different clusters which would have nothing to do with each other. The `marsadm` tool protects you against accidentally joining / merging two different clusters. If you accidentally created two different clusters, just unmount that `/mars/` partition and start over with step 3 at that node.
6. On node B, you must have a working `ssh` connection to node A. Test it by saying `ssh A w` on node B. It should work without entering a password (otherwise, use `ssh-agent` to achieve that). In addition, `rsync` must be installed.
7. On node B, say `marsadm join-cluster A`
8. Only *after*⁶ that, do `modprobe mars` on each node.

load in combination with high memory pressure.

⁴Internal DRBD metadata should also work as long as the filesystem inside your block device / disk already exists and is not re-created. The latter would destroy the DRBD metadata, but even that will not hurt you really: you can always switch back to DRBD using *external* metadata, as long as you have some small spare space somewhere.

⁵You should be familiar with the problems arising from orthogonal combination of different kernel versions with different MARS module versions and with different `marsadm` userspace tool versions at the package management level. Hint: `modinfo` is your friend.

⁶In fact, you may already `modprobe mars` at node A after the `marsadm create-cluster`. Just don't do any of the `*-cluster` operations when the kernel module is loaded. All other operations should have no such restriction.

2.3. Creating and Maintaining Resources

In the following example session, a block device `/dev/lv-x/mydata` (shortly called *disk*) must already exist on both nodes A and B, respectively, having the same⁷ size. For the sake of simplicity, the disk (underlying block device) as well as its later logical resource name as well as its later virtual device name will all be named uniformly by the same suffix `mydata`. In general, you might name each of them differently, but that is not recommended since it may easily lead to confusion in larger installations.

You may have already some data inside your disk `/dev/lv-x/mydata` at the initially primary side A. Before using it for MARS, it must be unused for any other purpose (such as being mounted, or used by DRBD, etc). MARS will require **exclusive access** to it.

1. On node A, say `marsadm create-resource mydata /dev/lv-x/mydata`.
As a result, a directory `/mars/resource-mydata/` will be created on node A, containing some symlinks. Node A will automatically start in the primary role for this resource. Therefore, a new pseudo-device `/dev/mars/mydata` will also appear after a few seconds. Note that the initial contents of `/dev/mars/mydata` will be exactly the same as in your pre-existing disk `/dev/lv-x/mydata`.
If you like, you may already use `/dev/mars/mydata` for mounting your already pre-existing data, or for creating a fresh filesystem, or for exporting via iSCSI, and so on. You may even do so before any other cluster node has joined the resource (so-called “standalone mode”). But you can also do so later after setup of (one or many) secondaries.
2. Wait a few seconds until the directory `/mars/resource-mydata/` and its symlink contents also appears on cluster node B.
3. On node B, say `marsadm join-resource mydata /dev/lv-x/mydata`.
As a result, the initial full-sync from node A to node B should start automatically.



Of course, your old contents of your disk `/dev/lv-x/mydata` at side B (and *only* there!) is overwritten by the version from side A. Since you are an experienced sysadmin, you knew that, and it was just the effect you deliberately wanted to achieve. If you didn't check that your old contents didn't contain any valuable data (or if you accidentally provided a wrong disk device argument), it is too late now. The `marsadm` command checks that the disk device argument is really a block device, and that exclusive access to it is possible (as well as some further safety checks, e.g. matching sizes). However, MARS cannot know the *purpose* of your generic block device. MARS (as well as DRBD) is completely ignorant of the *contents* of a generic block device; it does not interpret it in any way. Therefore, you may use MARS (as well as DRBD) for mirroring Windows filesystems, or raw devices from databases, or whatever.



Hint: by default, MARS uses the so-called “fast fullsync” algorithm. It works similar to `rsync`, first reading the data on both sides and computing an md5 checksum for each block. Heavy-weight data is only transferred over the long-distance network upon checksum mismatch. This is extremely fast if your data is already (almost) identical on both sides. Conversely, if you know in advance that your initial data is completely different on both sides, you may choose to switch off the fast fullsync algorithm via `echo 0 > /proc/sys/mars/do_fast_fullsync` in order to save the additional IO overhead and network latencies introduced by the separate checksum comparison steps.

4. Optionally: if you create a *new* filesystem on `/dev/mars/mydata` *after(!)* having created the MARS resource, you may skip the fast fullsync phase at all, because the old content of `/dev/mars/mydata` is just garbage not used by the freshly created filesystem. Just say `marsadm fake-sync mydata` in order to abort the sync operation.



Never do a `fake-sync` unless you are **absolutely sure** that you really don't need

⁷Actually, the disk at the initially secondary side may be larger than that at the initially primary side. This will waste space and is therefore not recommended.

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the data! Otherwise, you are almost *guaranteed* to have produced harmful inconsistencies. If you accidentally issued `fake-sync`, you may startover the full sync at your secondary side at any time by saying `marsadm invalidate mydata` (analogously to the corresponding DRBD command).

2.4. Keeping Resources Operational

2.4.1. Logfile Rotation / Deletion

As explained in section [The Transaction Logger](#), all changes to your resource data are recorded in transaction logfiles residing on the `/mars/` filesystem. These files are always growing over time. In order to avoid filesystem overflow, the following must be done in regular time intervals:

1. `marsadm log-rotate all`

This starts appending to a new logfile on all of your resources. The logfiles are automatically numbered by an increasing 9-digit logfile number. This will suffice for many centuries even if you would logrotate once a minute. Practical frequencies for logfile rotation are more like once an hour⁸, or once a day (depending on your load).

2. `marsadm log-delete-all all`

This determines all logfiles from all resources which are no longer needed (i.e. which are *fully* applied, on *all* relevant secondaries). All superfluous logfiles are then deleted, including all copies on all secondaries.



The current version of MARS deletes either *all* replicas of a logfile everywhere, or *none* of the replicas. This is a simple rule, but has the drawback that one node may hinder other nodes from freeing space in `/mars/`. In particular, the command `marsadm pause-replay $res` (as well as `marsadm disconnect $res`) will freeze the space reclamation in the whole cluster when the pause is lasting very long.



Best practice is to do both `log-rotate` and `log-delete-all` in a cron job. In addition, you should establish some regular monitoring of the free space present in the `/mars/` filesystem.

More detailed information about avoidance of `/mars/` overflow is in section [3.4](#).

2.4.2. Switch Primary / Secondary Roles

MARS Light distinguishes between *intended* and *emergency* switching. This distinction is necessary due to subtle differences in the communication architecture (synchronous communication vs asynchronous communication, see sections [3.2](#) and [3.3](#)).

2.4.2.1. Intended Switching

Switching the roles is very similar to DRBD: just issue the command

- `marsadm primary mydata`

on your formerly secondary node. Precondition is that the old primary must not use its `/dev/mars/mydata` device any longer. If that precondition is violated, `marsadm primary` refuses to run.

The reason for this check is that we want to avoid split brain situation as well as we can. Therefore, we distinguish between *intended* and *emergency* switching. Intended switching will try to avoid split brain as best as it can.

Notice that the usage check for `/dev/mars/mydata` is based on the open count transferred from another cluster node. Since MARS is operating asynchronously (in contrast to DRBD), it

⁸Under *extremely* high load conditions, you might want to log-rotate several times an hour, in order to keep the size of each logfile under some practical limit. At 1&1 datacenters, we have not yet encountered conditions where that was really *necessary*.

may take some time our node knows that the device is no longer used at another node. This can lead to a race condition if you automate an intended takeover with a script like `ssh A "umount /dev/mars/mydata"; ssh B "marsadm primary mydata"` because your second `ssh` command may be faster than the internal MARS symlink tree propagation (cf section 3.3). In order to prevent such races, you should use the command

- `marsadm wait-umount mydata`

on node B before trying to become primary. The script should look like `ssh A "umount /dev/mars/mydata"; ssh B "marsadm wait-umount mydata && marsadm primary mydata"`.

2.4.2.2. Emergency Switching

In case the connection to the old primary is lost, we just don't know anything about its *current* state (which may deviate from its *last known* state). The following variant will skip almost all checks and tell your node to become primary forcefully:

- `marsadm primary mydata --force`

This may lead to split brain if the old primary continues to operate on its local `/dev/mars/mydata` device. Therefore, you should do this only after

1. `marsadm primary` without `--force` has failed, and
2. you are sure you really want to switch even when that leads to a split brain. Notice that in case of connection loss you might not be able to reliably detect whether a split brain will actually result, or not.

In contrast to DRBD, split brain situations are handled differently by MARS Light. When two primaries are active at the same time, each of them writes into different logfiles `/mars/resource-mydata/log-0000` and `/mars/resource-mydata/log-000000001-B` where the *origin* host is always recorded in the filename. Therefore, both nodes *can* run in primary mode indepently from each other, at least for some time. They may even `log-rotate` independently from each other. However, any other secondary node gets into some problems then: it simply does not know whom it should follow.

Split brains are detected *passively* by secondaries. Whenever a secondary detects that somewhere a split brain has happend, it just refuses to to apply any logfiles behind the split point. This means that its local disk state will remain consistet, but outdated which respect to any of the split brain versions.

2.4.3. Split Brain Resolution

Whenever split brain occurs, you have two choices for resolution: either destroy one of your versions, or keep it under a different resource name.

2.4.3.1. Destroying a Split Brain Version

Do the following steps:

1. Manually check which version is the "right" one.
2. It may happen that the "right" version is not the version which is currently designated as primary for the whole cluster. In this case (or if you want to ensure nothing can go wrong), say `marsadm primary mydata --force` on the node you want to become the surviving "right" version. This should always work, even it is already the "right" primary.
3. On each other (non-"right") version, say `marsadm invalidate mydata`. Do this only when split brain has actually occurred at that node; otherwise an unnecessary full sync will start which was not really needed.

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2.4.3.2. Keeping a Split Brain Version

Do the following steps:

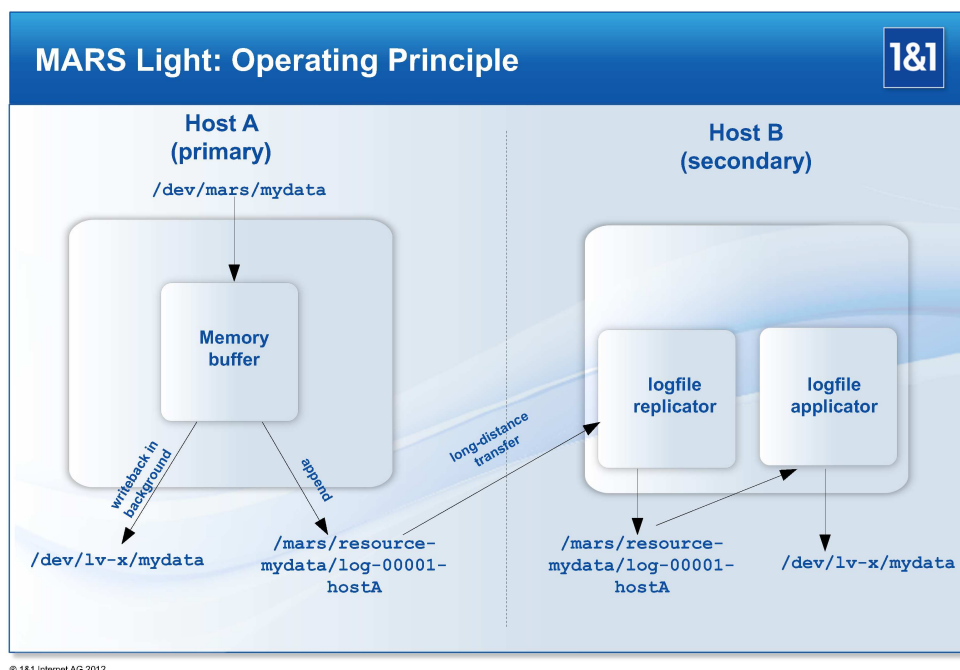
1. Manually check which version is the “right” one.
2. It may happen that the “right” version is not the version which is currently designated as primary for the whole cluster. In this case (or if you want to ensure nothing can go wrong), say `marsadm primary mydata --force` on *exactly that* node which you want to become the surviving “right” version.
3. On the non-right version which you want to retain, unmount your `/dev/mars/mydata`.
4. Wait until it reaches secondary state and its local logfile has been fully applied. This should happen because of step 2.
5. `marsadm leave-resource mydata`
6. Check that the underlying disk `/dev/lv-x/mydata` is really usable, e.g. by test-mounting it. If all is OK, don’t forget to unmount it before proceeding with the next step.
7. Create a completely new MARS resource out of the underlying disk `/dev/lv-x/mydata` having a different name, such as `mynewdata` (see description in section [Creating and Maintaining Resources](#)).

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Even if you are impatient, please read this chapter. At the *surface*, MARS appears to be very similar to DRBD. It looks like almost being a drop-in replacement for DRBD.

When taking this naïvely, you could easily step into some trivial pitfalls, because the internal working principle of MARS is totally different from DRBD. Please forget (almost) anything you already know about the internal working principles of DRBD, and look at the very different working principles of MARS.

3.1. The Transaction Logger



The basic idea of MARS is to record all changes made to your block device in a so-called **transaction logfile**. *Any* write request is treated like a transaction which changes the contents of your block device.

This is similar in concept to some database systems, but there exists no separate “commit” operation: *any* write request is acting like a commit.

The picture shows the flow of write requests. Let’s start with the primary node.

Upon submission of a write request on `/dev/mars/mydata`, it is first buffered in a *temporary* memory buffer.

The temporary memory buffer serves multiple purposes:

- It keeps track of the order of write operations.
- Additionally, it keeps track of the positions in the underlying disk `/dev/lv-x/mydata`. In particular, it detects when the same block is overwritten multiple times.
- During pending write operation, any concurrent reads are served from the memory buffer.

After the write has been buffered in the temporary memory buffer, the main logger thread of the transaction logger creates a so-called *log entry* and starts an “append” operation on the

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transaction logfile. The log entry contains vital information such as the logical block number in the underlying disk, the length of the data, a timestamp, some header magic in order to detect corruption, the log entry sequence number, of course the data itself, and optional information like a checksum or compression information.

Once the log entry has been written through to the `/mars/` filesystem via `fsync()`, the application waiting for the write operation at `/dev/mars/mydata` is signalled that the write was successful.

This may happen even *before* the writeback to the underlying disk `/dev/lv-x/mydata` has started. Even when you power off the system right now, the information is not lost: it is present in the logfile, and can be reconstructed from there.

Notice that the order of log records present in the transaction log defines a total order among the write requests which is *compatible* to the partial order of write requests issued on `/dev/mars/mydata`.

Also notice that despite its sequential nature, the transaction logfile is typically *not* the performance bottleneck of the system: since appending to a logfile is almost purely sequential IO, it runs much faster than random IO on typical datacenter workloads.

In order to reclaim the temporary memory buffer, its content must be written back to the underlying disk `/dev/lv-x/mydata` somewhen. After writeback, the temporary space is freed. The writeback can do the following optimizations:

1. writeback may be in *any* order; in particular, it may be *sorted* according to ascending sector numbers. This will reduce the average seek distances of magnetic disks in general.
2. when the same sector is overwritten multiple times, only the “last” version need to be written back, skipping some intermediate versions.

In case the primary node crashes during writeback, it suffices to replay the log entries from some point in the past until the end of the transaction logfile. It does no harm if you accidentally replay some log entries twice or even more often: since the replay is in the original total order, any temporary inconsistency is *healed* by the logfile application.



In mathematics, the property that you can apply your logfile twice to your data (or even as often as you want), is called **idempotence**. This is a very desirable property: it ensures that nothing goes wrong when applying “too much” / starting your replay “too early”. Idempotence is even more beneficial: in case anything should go wrong with your data on your disk (e.g. IO errors), applying your logfile once more often may¹ even **heal** some defects. Good news for desperate sysadmins forced to work with flaky hardware!

The basic idea of the asynchronous replication of MARS is rather simple: just transfer the logfiles to your secondary nodes, and apply them to their copy of the disk data (also called *mirror*) in the same order as the total order defined by the primary.

Therefore, a mirror of your data on any secondary may be outdated, but it always corresponds to some version which was valid in the past. This property is called **anytime consistency**².



As you can see in the picture, the process of transferring the logfiles is *independent* from the process which applies the logfiles to the data at some secondary site. Both processes can be switched on / off separately (see commands `marsadm {dis,}connect` and `marsadm {pause,resume}-replay` in section 4.2.2). This may be *exploited*: for example, you may replicate your logfiles as soon as possible (to protect against catastrophic failures), but deliberately wait one hour until it is applied (under regular circumstances). If your data inside your filesystem `/mydata/` at the primary site is accidentally destroyed by `rm -rf /mydata/`, you have an

¹Miracles cannot be guaranteed, but *higher chances* and *improvements* can be expected (e.g. better chances for `fsck`).

²Your secondary nodes are always consistent in themselves. Notice that this kind of consistency is a *local* consistency model. There exists no global consistency in MARS. Global consistency would be practically impossible in long-distance replication where Einstein’s law of the speed of light is limiting global consistency. The front-cover pictures showing the planets Earth and Mars tries to lead your imagination away from global consistency models as used in “DRBD Think(tm)”, and try to prepare you mentally for local consistency as in “MARS Think(tm)”.

old copy at the secondary site. This way, you can substitute *some parts*³ of conventional backup functionality by MARS. In case you need the actual version, just replay in “fast-forward” mode (similar to old-fashioned video tapes).



Future versions of MARS Full are planned to also allow “fast-backward” rewinding, of course at some cost.

3.2. The Lamport Clock

MARS is always *asynchronously* communicating in the distributed system on *any* topics, even strategic decisions.

If there were a *strict* global consistency model, which is roughly equivalent to a standalone model, we would need *locking* in order to serialize conflicting requests. It is known for many decades that *distributed locks* do not only suffer from performance problems, but they are also cumbersome to get them working reliably in scenarios where nodes or network links may fail at any time.

Therefore, MARS uses a very different consistency model: **Eventually Consistent**.

In order to implement that consistency model, MARS uses a so-called Lamport⁴ clock. MARS uses a special variant called “physical Lamport clock”.

The physical Lamport clock is another almost-realtime clock which *can* run independently from the Linux kernel system clock. However, the Lamport clock tries to remain as near as possible to the system clock.

Both clocks can be queried at any time via `cat /proc/sys/mars/lamport_clock`. The result will show both clocks in parallel, in units of seconds since the Unix epoch, with nanosecond resolution.

When there are no network messages at all, both the system clock and the Lamport clock will show almost the same time (except some minor differences of a few nanoseconds resulting from the finite processor clock speed).

The physical Lamport clock works rather simple: *any* message on the network is augmented with a Lamport time stamp telling when the message was *sent* according to the local Lamport clock of the sender. Whenever that message is received by some receiver, it checks whether the time ordering relation would be violated: whenever the Lamport timestamp in the message would claim that the sender had sent it *after* it arrived at the receiver (according to drifts in their respective local clocks), something must be wrong. In this case, the local Lamport clock of the *receiver* is advanced shortly after the sender Lamport timestamp, such that the time ordering relation is no longer violated.

As a consequence, any local Lamport clock may precede the corresponding local system clock. In order to avoid accumulation of deltas between the Lamport and the system clock, the Lamport clock will run slower after that, possibly until it reaches the system clock again (if no other message arrives which sets it forward again). After having reached the system clock, the Lamport clock will continue with “normal” speed.

MARS uses the local Lamport clock for anything where other systems would use the local system clock: for example, timestamp generation in the `/mars/` filesystem. Even symlinks created there are timestamped according to the Lamport clock. Both the kernel module and the userspace tool `marsadm` are always operating in the timescale of the Lamport clock. Most importantly, all timestamp comparisons are always carried out with respect to Lamport time.



Bigger differences between the Lamport and the system clock can be annoying from a human point of view: when typing `ls -l /mars/resource-mydata/` many timestamps may appear as if they were created in the “future”, because the `ls` command compares the output formatting against the system clock (it does not even know of the existence of the MARS Lamport clock).

³Please note that MARS cannot *fully* substitute a backup system, because it can keep only *physical* copies, and does not create logical copies.

⁴Published in the late 1970s by Leslie Lamport, also known as inventor of L^AT_EX.

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Always use `ntp` (or another clock synchronization service) in order to pre-synchronize your system clocks as close as possible. Bigger differences are not only annoying, but may lead some people to wrong conclusions and therefore even lead to bad human decisions!

In a professional datacenter, you should use `ntp` anyway, and you should monitor its effectiveness anyway.



Hint: many internal logfiles produced by the MARS kernel module contain Lamport timestamps written as numerical values. In order to convert them into human-readable form, use the command `marsadm cat /mars/5.total.status` or similar.

3.3. The Symlink Tree

The `/mars/` filesystem contains not only transaction logfiles, but also acts as a generic storage for (persistent) state information. Both configuration information and runtime state information are stored in symlinks. Symlinks are “misused⁵” in order to represent some `key -> value` pairs.



Therefrom results a fundamentally different behaviour than DRBD. When your DRBD primary crashed before and now comes up again, you have to setup DRBD again by a sequence of commands like `modprobe drbd; drbdadm up all; drbdadm primary all` or similar. In contrast, MARS needs only `modprobe mars` (after `/mars/` has been mounted by `/etc/fstab`). The *persistence* of the symlinks residing in `/mars/` will automatically remember your previous state, even if some your resources were primary while others were secondary (mixed operations). You don’t need to do any actions in order to “restore” a previous state, no matter how “complex” it was.

(Almost) all symlinks appearing in the `/mars/` directory tree are automatically replicated throughout the whole cluster. Thus the `/mars/` directory forms some kind of *global namespace*.

Since the symlink replication works generically, you may use the `/mars/userspace/` directory in order to place your own symlink there (for whatever purpose, which need not have to do with MARS).

In order to avoid name clashes, each symlink created at node A should have the name A in its path name. Typically, internal MARS names follow the scheme `/mars/something/myname-A`, and you should follow the best practice of systematically using `/mars/userspace/myname-A` or similar. As a result, each node will automatically get informed about the state at any other node, like B when the corresponding information is recorded on node B under the name `/mars/userspace/myname-B` (context-dependent names).



Important: the convention of placing the **creator host name** inside your symlink names should be used wherever possible. The name part is a kind of “ownership indicator”. It is crucial that no other host writes any symlink not “belonging” to him. Other hosts may read foreign symlinks as often as they want, but never modify them. This way, your cluster nodes are able to *communicate* with each other via symlink updates.

Although you may create (and change) your symlinks with userspace tools like `ln -s`, you should use the following `marsadm` commands instead:

- `marsadm set-link myvalue /mars/userspace/mykey-A`
- `marsadm delete-file /mars/userspace/mykey-A`

There are two reasons for this: first, the `marsadm set-link` command will automatically use the Lamport clock for symlink creation, and therefore will avoid any errors resulting from a “wrong” system clock (as in `ln -s`). Second, the `marsadm delete-file` (which also deletes symlinks) works on the *whole cluster*.

⁵This means, the symlink targets need not be other files or directories, but just any values like integers or strings.

What’s the difference? If you try to remove your symlink locally by hand via `rm -f`, you will be surprised: since the symlink has been replicated to other cluster nodes, it will be re-transferred from there and will be resurrected locally after some short time. This way, you cannot delete any object reliably, because your whole cluster (which may consist of many nodes) remembers all your state information and will resurrect it whenever “necessary”.

In order to solve the deletion problem, MARS Light uses some internal deletion protocol using auxiliary symlinks residing in `/mars/todo-global/`. The deletion protocol ensures that all replicas get deleted in the whole cluster, and only after that the auxiliary symlinks in `/mars/todo-global/` are also deleted eventually.

You may change your already existing symlink via `marsadm set-link some-other-value /mars/userspace/mykey-A`. The new value will be propagated in the cluster according to a **timestamp comparison protocol**: whenever node B notices that A has a *newer* version of some symlink (according to the Lamport timestamp), it will replace its elder version by the newer one. The opposite does *not* work: if B notices that A has an elder version, just nothing happens. This way, the timestamps of symlinks can only progress in forward direction, but never backwards in time.

As a consequence, symlink updates made “by hand” via `ln -s` may get lost when the local system clock is much more earlier than the Lamport clock.

When your cluster is fully connected by the network, the last timestamp will finally win everywhere. Only in case of network outages leading to *network partitions*, some information may be *temporarily inconsistent*, but only for the duration of the network outage. The timestamp comparison protocol in combination with the Lamport clock and with the persistence of the `/mars/` filesystem will automatically heal any temporary inconsistencies as soon as possible, even in case of temporary node shutdown.

The meaning of the internal MARS Light symlinks residing in `/mars/` is documented in section 5.2.

3.4. Defending Overflow of `/mars/`

This section describes an important difference to DRBD. The metadata of DRBD is allocated *statically at creation time* of the resource. In contrast, the MARS transaction logfiles are allocated *dynamically at runtime*.

This leads to a potential risk from the perspective of a sysadmin: what happens if the `/mars/` filesystem runs out of space?

No risk, no fun. If you want a system which survives long-lasting network outages while keeping your replicas always consistent (anytime consistency), you *need* dynamic memory for that. It is *impossible* to solve that problem using static memory⁶.

Therefore, DRBD and MARS have different application areas. If you just want a simple system for mirroring your data over short distances like a crossover cable, DRBD will be a suitable choice. However, if you need to replicate over longer distances, or if you need higher levels of reliability even when multiple failures may accumulate (such as network loss during a resync of DRBD), the transaction logs of MARS can solve that, but at some *cost*.

3.4.1. Countermeasures

3.4.1.1. Dimensioning of `/mars/`

The first (and most important) measure against overflow of `/mars/` is simply to dimension it large enough to survive longer-lasting problems, at least one weekend.

Recommended size is at least one dedicated disk, residing at a hardware RAID controller with BBU (see section 2.1). During normal operation, that size is needed only for a small fraction, typically a few percent or even less than one percent. However, it is your **safety margin**. Keep it high enough!

⁶The bitmaps used by DRBD don’t preserve the *order* of write operations. They cannot do that, because their space is $O(k)$ for some constant k . In contrast, MARS preserves the order. Preserving the order as such (even when only *facts* about the order were recorded without recording the actual data contents) requires $O(n)$ space where n is infinitely growing over time.

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3.4.1.2. Monitoring

The next (equally important) measure is **monitoring in userspace**.

Following is a list of countermeasures both in userspace and in kernelspace, in the order of “defensive walling”:

1. Regular userspace monitoring must throw an INFO if a certain freespace limit l_1 of `/mars/` is undershot. Typical values for l_1 are 30%. Typical actions are automated calls of `marsadm log-rotate all` followed by `marsadm log-delete-all all`. You have to implement that yourself in sysadmin space.
2. Regular userspace monitoring must throw a WARNING if a certain freespace limit l_2 of `/mars/` is undershot. Typical values for l_2 are 20%. Typical actions are (in addition to `log-rotate` and `log-delete-all`) alarming human supervisors via SMS and/or further stronger automated actions.



Frequently large space is occupied by files stemming from debugging output, or from other programs or processes. A hot candidate is “forgotten” removal of debugging output to `/mars/`. Sometimes, an `rm -rf $(find /mars/ -name ‘*.log’)` can work miracles.



Another source of space hogging is a “forgotten” `pause-sync` or `disconnect`. Therefore, a simple `marsadm connect-global all` followed by `marsadm resume-replay-global all` may also work miracles (if you didn’t want to freeze some mirror deliberately).



If you just wanted to freeze a mirror at an outdated state for a very long time, you simply *cannot* do that without causing infinite growth of space consumption in `/mars/`. Therefore, a `marsadm leave-resource $res` at *exactly that(!)* secondary site where the mirror is frozen, can also work miracles. If you want to automate this in userspace, be careful. It is easy to get unintended effects when choosing the wrong site for `leave-resource`.



Hint: you can / should start some of these measures even earlier at the INFO level (see item 1), or even earlier.

3. Regular userspace monitoring must throw an ERROR if a certain freespace limit l_3 of `/mars/` is undershot. Typical values for l_3 are 10%. Typical actions are alarming the CEO via SMS and/or even stronger automated actions. For example, you may choose to automatically call `marsadm leave-resource $res` on some or all secondary nodes, such that the primary will be left alone and now has a chance to really delete its logfiles because no one else is any longer potentially needing it.
4. First-level kernelspace action, automatically executed when `/proc/sys/mars/required_free_space_4_gb + /proc/sys/mars/required_free_space_3_gb + /proc/sys/mars/required_free_space_2_gb + /proc/sys/mars/required_free_space_1_gb` is undershot:
all locally secondary resources will stop fetching transaction logfiles. As a side effect, other nodes in the cluster may become unable to delete their logfiles also. This is a desperate action of the kernel module.
5. Second-level kernelspace action, automatically executed when `/proc/sys/mars/required_free_space_3_gb + /proc/sys/mars/required_free_space_2_gb + /proc/sys/mars/required_free_space_1_gb` is undershot:
all locally secondary resources will start removing any logfiles which are no longer used locally. This is a more desperate action of the kernel module.

6. Third-level kernelspace action, automatically executed when `/proc/sys/mars/required_free_space_2_gb` + `/proc/sys/mars/required_free_space_1_gb` is undershot: all locally primary resources are checked for logfiles which are no longer needed *locally*. Locally unneeded files are deleted even when some secondary needs them. As a consequence, some secondaries may get stuck (left in consistent, but outdated state). In order to get them actual again, they will need a `marsadm invalidate` later. This is an even more desperate action of the kernel module. You don't want to get there (except for testing).
7. Last desperate kernelspace action when all other has failed and `/proc/sys/mars/required_free_space_1_gb` is undershot: all locally primary resources will enter **emergency mode** (see description below in section 3.4.2). This is the most desperate action of the kernel module. You don't want to get there (except for testing).

In addition, the kernel module obeys a general global limit `/proc/sys/mars/required_total_space_0_gb` + the sum of all of the above limits. When the *total size* of /mars/ undershots that sum, the kernel module refuses to start at all, because it assumes that it is senseless to try to operate MARS on a system with such low memory resources.



The current level of emergency kernel actions may be viewed at any time via `/proc/sys/mars/mars_emergency_mode`.

3.4.1.3. Throttling

The last measure for defense of overflow is **throttling your performance pigs**.

Motivation: in rare cases, some users with `ssh` access can do *very* silly things. For example, some of them are creating their own backups via user-cron jobs, and they do it every 5 minutes. Some example guy created a zip archive (almost 1GB) by regularly copying his old zip archive into a new one, then appending deltas to the new one, and finally deleting the old archive. Every 5 minutes. Yes, every 5 minutes, although almost never any new files were added to the archive. Essentially, he copied over his archive, for nothing. This led to massive bulk write requests, for ridiculous reasons.

In general, your hard disks (or even RAID systems) allow much higher write IO rates than you can ever transport over a standard TCP network from your primary site to your secondary, at least over longer distances (see use cases for MARS in chapter 1). Therefore, it is easy to create a such a high write load that it will be *impossible* to replicate it over the network, *by construction*.

Therefore, we *need* some mechanism for throttling bulk writers whenever the network is weaker than your IO subsystem.



Notice that DRBD will *always* throttle your writes whenever the network forms a bottleneck, due to its synchronous operation mode. In contrast, MARS allows for buffering of performance peaks in the transaction logfiles. *Only when* your buffer in /mars/ runs short (cf subsection 3.4.1.1), MARS will start to throttle your application writes.

There are a lot of screws named `/proc/sys/mars/write_throttle_*` with the following meaning:

write_throttle_start_percent Whenever the used space in /mars/ is below this threshold, no throttling will occur at all. Only when this threshold is exceeded, throttling will start *slowly*. Typical values for this are 60%.

write_throttle_end_percent Maximum throttling will occur once this space threshold is reached, i.e. the throttling is now at its maximum effect. Typical values for this are 90%. When the actual space in /mars/ lies between `write_throttle_start_percent` and `write_throttle_end_percent`, the strength of throttling will be interpolated linearly between the extremes. In practice, this should lead to an equilibrium between new input flow into /mars/ and output flow over the network to secondaries.

3. Basic Working Principle

`write_throttle_size_threshold_kb` (readonly) This parameter shows the internal strength calculation of the throttling. Only write⁷ requests exceeding this size (in KB) are throttled at all. Typically, this will hurt the bulk performance pigs first, while leaving ordinary users (issuing small requests) unaffected.

`write_throttle_ratelimit_kb` Set the global IO rate in KB/s for those write requests which are throttled. In case of strongest⁸ throttling, this parameters determines the input flow into `/mars/`. The default value is 5.000 KB/s. Please adjust this value to your application needs and to your environment.

`write_throttle_rate_kb` (readonly) Shows the current rate of exactly those requests which are actually throttled (in contrast to *all* requests).

`write_throttle_cumul_kb` (logically readonly) Same as before, but the cumulative sum of all throttled requests since startup / reset. This value can be reset from userspace in order to prevent integer overflow.

`write_throttle_count_ops` (logically readonly) Shows the cumulative number of throttled requests. This value can be reset from userspace in order to prevent integer overflow.

`write_throttle_maxdelay_ms` Each request is delayed at most for this timespan. Smaller values will improve the responsiveness of your userspace application, but at the cost of potentially retarding the requests not sufficiently.

`write_throttle_minwindow_ms` Set the minimum length of the measuring window. The measuring window is the timespan for which the average (throughput) rate is computed (see `write_throttle_rate_kb`). Lower values can increase the responsiveness of the controller algorithm, but at the cost of accuracy.

`write_throttle_maxwindow_ms` This parameter must be set sufficiently much greater than `write_throttle_minwindow_ms`. In case the flow of throttled operations pauses for some natural reason (e.g. switched off, low load, etc), this parameter determines when a completely new rate calculation should be started over⁹.

3.4.2. Emergency Mode

When `/mars/` is almost full and there is really absolutely no chance of getting rid of any local transaction logfile (or free some space in any other way), there is only one exit strategy: stop creating new logfile data.

This means that the ability for replication gets lost.

When entering emergency mode, the kernel module will execute the following steps for all resources where the affected host is acting as a primary:

1. Do a kind of “logrotate”, but create a *hole* in the sequence of transaction logfile numbers. The “new” logfile is left empty, i.e. no data ist written to it (for now). The hole in the numbering will prevent any secondaries from applying any logfiles behind the hole (should they ever contain some data, e.g. because the emergency mode has been left again). This works because the secondaries are regularly checking the logfile numbers for contiguity, and they will refuse to apply anything which is not contiguous. As a result, the secondaries will be left in a consistent, but outdated state.
2. The kernel module writes back all data present in the temporary memory buffer (see figure in section 3.1). This may lead to a (short) delay of user write requests until that has finished (typically fractions of a second or a few seconds). The reason is that the temporary memory buffer must not be increased in parallel during this phase (race conditions).

⁷Read requests are never throttled at all.

⁸In case of lighter throttling, the input flow into `/mars/` may be higher because small requests are not throttled.

⁹Motivation: if requests would pause for one hour, the measuring window could become also an hour. Of course, that would lead to completely meaningless results. Two requests in one hour is “incorrect” from a human point of view: we just have to ensure that averages are computed with respect to a reasonable maximum time window in the magnitude of 10s.

3. After the temporary memory buffer is empty, all local IO requests (whether reads or writes) are directly going to the underlying disk. This has the same effect as if MARS was not present anymore.

In order to leave emergency mode, the sysadmin should do the following steps:

1. Free enough space. For example, delete any foreign files on /mars/ which have nothing to do with MARS, or resize the /mars/ filesystem, or whatever.
2. If `/proc/sys/mars/mars_reset_emergency` is not set, now it is time to set it. Normally, it should be already set. In consequence, the primary sides should continue transaction logging automatically.
3. On the secondaries, use `marsadm invalidate $res` in order to get your outdated mirrors uptodate. This will lead to temporarily inconsistent mirrors, so don't do this on all secondaries in parallel, but sequentially step by step. This way, if you have more than 1 mirror, you will always retain at least one consistent, but outdated copy.




If you had only 1 mirror per resource before the overflow happened, you can now create a new one via `marsadm join-resource $res` on a third node (provided that your storage space permits that after the cleanup). After the initial full sync has finished there, do an `marsadm invalidate $res` on the outdated mirror. This way, you will always retain at least one consistent mirror somewhere. After all is up-to-date, you can delete the superfluous mirror by `marsadm leave-resource $res` and reclaim the disk space from its underlying disk.

4. The Sysadmin Interface marsadm

In general, the term “after a while” means that other cluster nodes will take notice of your actions according to the “eventually consistent” propagation protocol described in sections 3.2 and 3.3. Please be aware that this “while” may last very long in case of network outages or bad firewall rules.

In the following tables, column “Cmp” means compatibility with DRBD. Please note that 100% exact compatibility is not possible, because of the asynchronous communication paradigm.

The following table documents common options which work with (almost) any command:

Option	Cmp	Description
<code>--force</code>	almost	Some preconditions are skipped, i.e. the command will / should work although some (more or less) vital preconditions are violated. Instead of giving <code>--force</code> , you may alternatively prefix your command with <code>force-</code>  THIS OPTION IS DANGEROUS! Use it only when you are absolutely sure that you know what you are doing! Use it only as a last resort if the same command without <code>--force</code> has failed!
<code>--timeout=\$seconds</code>	no	Some commands require response from either the local kernel module, or from other cluster nodes. In order to prevent infinite waiting in case of network outages or other problems, the command will fail after the given timeout has been reached. When <code>\$seconds</code> is -1, the command will wait forever. When <code>\$seconds</code> is 0, the command will not wait in case any precondition is not met, und abort without performing an action.. <u>The default timeout is 5s.</u>
<code>--host=\$host</code>	no	The command acts as if the command were executed on another host <code>\$host</code> . This option should not be used regularly, because the local information in the symlink tree may be outdated or even wrong, and some local information like sizes of physical devices (e.g. disks) is not present in the symlink tree. Use at your own risk!
<code>--verbose</code>	no	Some (few) commands will become more speaky.
Option	Cmp	Description

4.1. Cluster Operations

Command / Params	Cmp	Description
<code>create-cluster</code>	no	Precondition: the <code>/mars/</code> filesystem must be mounted and it must be empty. The kernel module must not be loaded. Postcondition: the initial symlink tree is created in <code>/mars/</code> . Additionally, the <code>/mars/uuid</code> symlink is created for later distribution in the cluster. It uniquely identifies the cluster in the world. This must be called exactly once at the initial primary.
<code>join-cluster</code> <code>\$host</code>	no	Precondition: the <code>/mars/</code> filesystem must be mounted and it must be empty. The kernel module must not be loaded. The cluster must have been already created at another node <code>\$host</code> . A working ssh connection to <code>\$host</code> must exist (without password). <code>rsync</code> must be installed at all cluster nodes. Postcondition: the initial symlink tree <code>/mars/</code> is replicated from the remote host <code>\$host</code> , and the local host has been added as another cluster member. This must be called exactly once at every initial secondary.
Command / Params	Cmp	Description

Command / Params	Cmp	Description
<code>leave-cluster</code>	no	<p>Precondition: the <code>/mars/</code> filesystem must be mounted and it must contain a valid MARS symlink tree produced by the other <code>marsadm</code> commands. The kernel module must be loaded. The local node must no longer be member of any resource (see <code>marsadm leave-resource</code>).</p> <p>Postcondition: the local node is removed from the replicated symlink tree <code>/mars/</code> such that other nodes will cease to communicate with it after a while. The local <code>/mars/</code> filesystem may be finally destroyed.</p> <p>In case of an eventual node loss (e.g. fire, water, ...) this may be used. on another node <code>\$helper</code> in order to finally remove <code>\$damaged</code> from the cluster via the command <code>marsadm leave-cluster --host=\$damaged --force</code>.</p>
<code>wait-cluster</code>	no	See section 4.3.2.
Command / Params	Cmp	Description

4.2. Resource Operations

Common precondition for all resource operations is that the `/mars/` filesystem is mounted, that it contains a valid MARS symlink tree produced by other `marsadm` commands, that your current node is a member of the cluster, and that the kernel module is loaded. When communication is impossible due to network outages or bad firewall rules, most commands will succeed, but other cluster nodes may take a long time to notice your changes.




4.2.1. Resource Creation / Deletion / Modification



Command / Params	Cmp	Description
<code>create-resource</code> <code>\$res</code> <code>\$disk_dev</code> <code>[\$mars_name]</code> <code>[\$size]</code>	no	<p>Precondition: the resource argument <code>\$res</code> must not denote an already existing resource in the cluster. The argument <code>\$disk_dev</code> must denote a usable local block device, its size must be greater zero. When the optional <code>\$mars_name</code> is given, that name must not already exist on the local node; when not given, <code>\$mars_name</code> defaults to <code>\$res</code>. When the optional <code>\$size</code> argument is given, it must be a number, optionally followed by suffix <code>k</code>, <code>m</code>, <code>g</code>, or <code>t</code> (denoting size factors in powers of two). The given size must not exceed the actual size of <code>\$disk_dev</code>.</p> <p>Postcondition: the resource <code>\$res</code> is created, the initial role of the current node is primary. The corresponding symlink tree information is asynchronously distributed in the cluster (in the background). The device <code>/dev/mars/\$mars_name</code> should appear after a while.</p> <p>Notice: when <code>\$size</code> is strictly smaller than the size of <code>\$disk_dev</code>, you will unnecessarily waste some space..</p> <p>This must be called exactly once for any new resource.</p>
<code>join-resource</code> <code>\$res</code> <code>\$disk_dev</code> <code>[\$mars_name]</code>	no	<p>Precondition: the resource argument <code>\$res</code> must denote an already existing resource in the cluster (i.e. its symlink tree information must have been received). The local node must not be already member of that resource. The argument <code>\$disk_dev</code> must denote a usable local block device, its size must be greater or equal to the logical size of the resource. When the optional <code>\$mars_name</code> is given, that name must not already exist on the local node; when not given, <code>\$mars_name</code> defaults to <code>\$res</code>.</p> <p>Postcondition: the current node becomes a member of resource <code>\$res</code>, the initial role is secondary. The initial full sync should start after a while.</p> <p>Notice: when the size if <code>\$disk_dev</code> is strictly greater than the size of the resource, you will unnecessarily waste some space..</p>
<code>leave-resource</code> <code>\$res</code>	no	<p>Precondition: the local node must be a member of the resource <code>\$res</code>; its current role must be secondary. The disk must be detached.</p> <p>Postcondition: the local node is no longer a member of <code>\$res</code>.</p> <p>Notice: as a side effect for other nodes, their log-delete .may now become possible, since the current node does no longer count as a candidate for logfile application.</p> <p>In case of an eventual node loss (e.g. fire, water, ...) this may be used. on another node <code>\$helper</code> in order to finally remove all the resources <code>\$damaged</code> from the cluster via the command <code>marsadm leave-resource \$res --host=\$damaged --force</code>.</p>
<code>wait-resource</code> <code>\$res</code> <code>{is-}{attach,</code> <code>primary,</code> <code>device}{-off,}</code>	no	See section 4.3.2.
Command / Params	Cmp	Description

4.2.2. Operation of the Resource

Common preconditions are the preconditions from section 4.2, plus the respective resource `$res` must exist, and the local node must be a member of it. With the single exception of `attach` itself, all other operations must be started in `attached` state.

When `$res` has the special reserved value `all`, the following operations will work on all resources where the current node is a member (analogously to DRBD).

Command / Params	Cmp	Description
<code>attach</code> <code>\$res</code>	yes	Precondition: the local disk belonging to <code>\$res</code> is not in use by anyone else. Postcondition: MARS uses the local disk and is able work with it (e.g. apply logfiles to it). Note: the local disk is opened in exclusive read-write mode. This should protect against most common misuse, such as opening the disk in parallel to MARS.
<code>detach</code> <code>\$res</code>	yes	Precondition: the local host is in secondary role, <code>pause-sync</code> and <code>pause-replay</code> have been given.. Postcondition: the local disk belonging to <code>\$res</code> is no longer in use.  WARNING! After this, you might use the underlying disk for other purposes, such as test-mounting it in <code>readonly</code> mode.. Don't modify its contents in any way! Not even by an <code>fsck</code> ! Otherwise, you will have inconsistencies <i>guaranteed</i> . MARS has no way for knowing of any modifications to your disk when not written via <code>/dev/mars/*</code> .  In case you accidentally modified the underlying disk at the <i>primary</i> side, you may choose to resolve the inconsistencies by <code>marsadm invalide \$res</code> on <i>each</i> secondary.
<code>pause-sync</code> <code>\$res</code>	partly	Equivalent to <code>pause-sync-local</code> .
<code>pause-sync-local</code> <code>\$res</code>	partly	Precondition: none additionally. Postcondition: any sync operation targeting the local disk (when not yet completed) is paused after a while. When completed, this operation will remember the switch state forever and become relevant if a sync is needed again (e.g. <code>invalidate</code> or <code>resize</code>).
<code>pause-sync-global</code> <code>\$res</code>	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>resume-sync</code> <code>\$res</code>	partly	Equivalent to <code>pause-sync-local</code> .
<code>resume-sync-local</code> <code>\$res</code>	partly	Precondition: none additionally. Postcondition: any sync operation targeting the local disk (when not yet completed) is resumed after a while. When completed, this operation will remember the switch state forever and become relevant if a sync is needed again (e.g. <code>invalidate</code> or <code>resize</code>).
<code>resume-sync-global</code> <code>\$res</code>	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>pause-replay</code> <code>\$res</code>	partly	Equivalent to <code>pause-replay-local</code> .
<code>pause-replay-local</code> <code>\$res</code>	partly	Precondition: must be in secondary role. Postcondition: any local apply operations of transaction logfiles to the local disk are paused at their current stage.  This works independently from <code>{dis,}connect</code> .
<code>pause-replay-global</code> <code>\$res</code>	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>resume-replay</code> <code>\$res</code>	partly	Equivalent to <code>pause-replay-local</code> .
Command / Params	Cmp	Description



Command / Params	Cmp	Description
<code>resume-replay-local</code> \$res	partly	Precondition: must be in secondary role. Postcondition: any (parts of) locally existing transaction logfiles (whether replicated from other hosts or produced locally) are started for apply to the local disk, as far as they have not yet been applied.
<code>resume-replay-global</code> \$res	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>connect</code> \$res	partly	Equivalent to <code>connect-local</code> .
<code>connect-local</code> \$res	partly	Precondition: must be in secondary role. Postcondition: any (parts of) transaction logfiles which are present at another primary host will be transferred to the local <code>/mars/</code> storage as far as not yet present locally.  This works independently from <code>{pause,resume}-replay</code> .
<code>connect-global</code> \$res	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>disconnect</code> \$res	partly	Equivalent to <code>disconnect-local</code> .
<code>disconnect-local</code> \$res	partly	Precondition: must be in secondary role. Postcondition: any transfer of (parts of) transaction logfiles which are present at another primary host to the local <code>/mars/</code> storage are paused at their current stage.  This works independently from <code>{pause,resume}-replay</code> .
<code>disconnect-global</code> \$res	partly	Like <code>*-local</code> , but operates on all members of the resource.
<code>up</code> \$res	yes	Equivalent to <code>attach</code> followed by <code>connect</code> followed by <code>resume-replay</code> followed by <code>resume-sync</code> .
<code>down</code> \$res	yes	Equivalent to <code>pause-sync</code> followed by <code>disconnect</code> followed by <code>pause-replay</code> followed by <code>detach</code> .
<code>primary</code> \$res	almost	Precondition: all relevant transaction logfiles must be either already locally present, or be fetchable (see <code>connect</code> and <code>resume-replay</code>). When another host is currently primary, it must match the preconditions of <code>marsadm secondary</code> . Postcondition: <code>/dev/mars/\$dev_name</code> appears and is usable; the current host is in primary role. When another host is currently primary, it is first asked to become secondary, and waited for to actually be secondary. After that, the local host is asked to become primary. Before actually becoming primary, all relevant logfiles are applied. Only after that, <code>/dev/mars/\$dev_name</code> will appear. When network transfers of the symlink tree are very slow (or currently impossible), this command may take a very long time. Therefore <code>--force</code> will skip all checks depending on remote state. In case a split brain is detected, the local host will refuse to become <code>primary</code> without <code>--force</code> .
<code>secondary</code> \$res	almost	Precondition: the local <code>/dev/mars/\$dev_name</code> is no longer in use (e.g. unmounted). Postcondition: <code>/dev/mars/\$dev_name</code> has disappeared; the current host is in secondary role.
<code>wait-umount</code> \$res	no	See section 4.3.2.
<code>resize</code> \$res [\$size]	almost	Precondition: all disks in the cluster participating in \$res must be physically larger than the logical resource size (e.g. by use of <code>lvm</code>). When the optional \$size argument is present, it must be smaller than the minimum of all physical sizes, but larger than the current logical size. Postcondition: at the (future) primary (if any), the logical size of <code>/dev/mars/\$dev_name</code> will reflect the new size after a while.
Command / Params	Cmp	Description

4. The Sysadmin Interface *marsadm*

4.2.3. Logfile Operations

Command / Params	Cmp	Description
<code>log-rotate</code> \$ <i>res</i>	no	Precondition: the local node <i>\$host</i> must be primary at <i>\$res</i> . Postcondition: after a while, a new transaction logfile <code>/mars/resource-<i>\$res</i>/log-<i>\$new_nr</i>-<i>\$host</i></code> will be used instead of <code>/mars/resource-<i>\$res</i>/log-<i>\$old_nr</i>-<i>\$host</i></code> where $\textit{new_nr} = \textit{old_nr} + 1$.
<code>log-delete</code> \$ <i>res</i>	no	Precondition: the local node must be a member of <i>\$res</i> . Postcondition: when there exists an old transaction logfile <code>/mars/resource-<i>\$res</i>/log-<i>\$old_nr</i>-<i>\$some_host</i></code> where <i>\$old_nr</i> is the minimum existing number and that logfile is no longer referenced by any of the symlinks <code>/mars/resource-<i>\$res</i>/replay-*</code> , that logfile is marked for deletion in the whole cluster. When no such logfile exists, nothing will happen.
<code>log-delete-all</code> \$ <i>res</i>	no	Like <code>log-delete</code> , but mark <i>all</i> currently unreferenced logfiles for deletion.
Command / Params	Cmp	Description

4.2.4. Consistency Operations

Command / Params	Cmp	Description
<code>invalidate</code> \$ <i>res</i>	no	Precondition: the local node must be in secondary role at <i>\$res</i> . Postcondition: the local disk is marked as inconsistent, and a fast fullsync will start after a while. Notice that <code>marsadm {pause,resume}-sync</code> will influence whether the sync really starts. When the fullsync has finished successfully, the local node will be consistent again.
<code>fake-sync</code> \$ <i>res</i>	no	Precondition: the local node must be in secondary role at <i>\$res</i> . Postcondition: when a fullsync is running, it will stop after a while, and the local node will be <i>marked</i> as consistent as if it were consistent again.  ONLY USE THIS IF YOU REALLY KNOW WHAT YOU ARE DOING! See the WARNING in section 2.3 Use this only <i>after</i> having created a fresh filesystem inside <code>/dev/mars/<i>\$res</i></code> .
<code>set-replay</code>	no	 ONLY FOR ADVANCED HACKERS WHO KNOW WHAT THEY ARE DOING! This command is deliberately not documented. You need the competence level RTFS (“read the fucking sources”).
Command / Params	Cmp	Description

4.3. Further Operations

4.3.1. Inspection Commands

Command / Params	Cmp	Description
<code>role</code>	no	
<code>state</code>	no	
<code>cstate</code>	no	NYI
<code>dstate</code>	no	NYI
<code>status</code>	no	NYI
<code>show-state</code>	no	
Command / Params	Cmp	Description

Command / Params	Cmp	Description
<code>show-info</code>	no	
<code>dstate</code>	no	
<code>show</code>	no	
<code>show-errors</code>	no	
<code>cat</code>	no	
Command / Params	Cmp	Description

4.3.2. Waiting

Command / Params	Cmp	Description
<code>wait-cluster</code>	no	Precondition: the <code>/mars/</code> filesystem must be mounted and it must contain a valid MARS symlink tree produced by the other <code>marsadm</code> commands. The kernel module must be loaded. Postcondition: none. Wait until <i>all</i> nodes in the cluster have sent a message, or until timeout. The default timeout is 30 s (exceptionally) and may be changed by <code>--timeout=\$seconds</code>
<code>wait-resource</code> <code>\$res</code> <code>{is-},{attach,</code> <code>primary,</code> <code>device}{-off,}</code>	no	Precondition: the local node must be a member of the resource <code>\$res</code> . Postcondition: none. Wait until the local node reaches a specified condition on <code>\$res</code> , or until timeout. The default timeout of 60 s may be changed by <code>--timeout=\$seconds</code> . The last argument denotes the condition. The condition is inverted if suffixed by <code>-off</code> . When preceded by <code>is-</code> (which is the most useful case), it is checked whether the condition is actually reached. When the <code>is-</code> prefix is left off, the check is whether another <code>marsadm</code> command has been already given which <i>tries</i> to achieves the intended result (typically, you may use this after the <code>is-</code> variant has failed).
<code>wait-connect</code> <code>\$res</code>	almost	This is an alias for <code>wait-cluster</code> waiting until only those nodes are reachable which belong to <code>\$res</code> (instead of waiting for the <i>full</i> cluster).
<code>wait-umount</code> <code>\$res</code>	no	Precondition: none additionally. Postcondition: the local <code>/dev/mars/\$dev_name</code> is no longer in use (e.g. unmounted).
Command / Params	Cmp	Description

4.3.3. Low-Level Helpers

These commands are for advanced sysadmins only. The interface is not stable, i.e. the meaning may change at any time.

Command / Params	Cmp	Description
<code>set-link</code>	no	
<code>delete-file</code>	no	
Command / Params	Cmp	Description

4.3.4. Senseless Commands (from DRBD)

Command / Params	Cmp	Description
<code>syncer</code>	no	
<code>new-current-uuid</code>	no	
<code>create-md</code>	no	
<code>dump-md</code>	no	
<code>dump</code>	no	
<code>get-gi</code>	no	
<code>show-gi</code>	no	
Command / Params	Cmp	Description

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Command / Params	Cmp	Description
<code>outdate</code>	no	
<code>adjust</code>	yes	Implemented as NOP (not necessary with MARS).
<code>hidden-commands</code>	no	
Command / Params	Cmp	Description

4.3.5. Forbidden Commands (from DRBD)

These commands are not implemented because they would be dangerous in MARS context:

Command / Params	Cmp	Description
<code>invalidate-remote</code>	no	This is too dangerous in case you have multiple secondaries. A similar effect can be achieved with the <code>--host=</code> option.
<code>verify</code>	no	This would cause unintended side effects due to races between log-file transfer / application and block-wise comparison of the underlying disks. However, MARS <code>invalide</code> will do the same as DRBD <code>verify</code> followed by DRBD <code>resync</code> , i.e. <code>marsadm invalidate</code> will automatically correct any found errors; note that the fast-fullsync algorithm of MARS will minimize network traffic.
Command / Params	Cmp	Description

4.3.6. Deprecated Operations

5. MARS for Developers

This chapter is organized strictly top-down.

If you are a sysadmin and want to inform yourself about internals (useful for debugging), the relevant information is at the beginning, and you don't need to dive into all technical details at the end (e.g., you may stop after reading the documentation on symlink trees or even use that documentation like an encyclopedia).

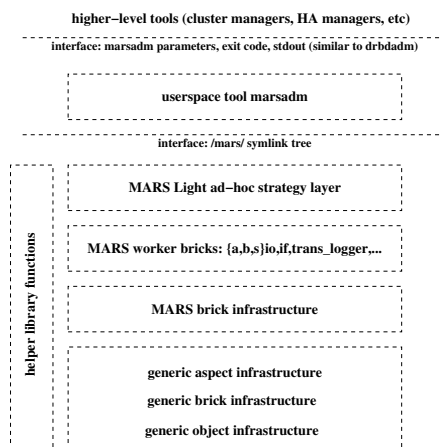
If you are a kernel developer and want to contribute code to the MARS community, please read it (almost) all. Due to the top-down organization, sometimes you will need to follow some forward references in order to understand details. Therefore I recommend reading this chapter twice in two different reading modes: in the first reading pass, you just get a raw network of principles and structures in your brain (you don't want to grasp details, therefore don't strive for a full understanding). In the second pass, you exploit your knowledge from the first pass for a deeper understanding of the details.

Alternatively, you may first read the first section about general architecture, and then start a bottom-up scan by first reading the last section about generic objects and aspects, and working in reverse *section* order (but read *subsections* in-order) until you finally reach the kernel interfaces / symlink trees.

5.1. General Architecture

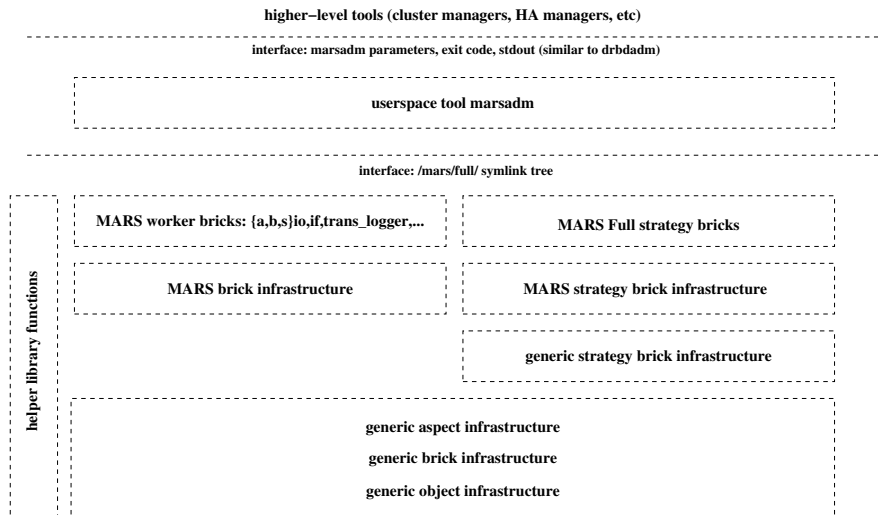
The following pictures show some “zones of responsibility”, not necessarily a strict hierarchy (although Dijkstra's famous layering rules from THE are tried to be respected as much as possible). The construction principles follow the concepts of **Instance Oriented Programming** (IOP) described in http://athomux.net/papers/paper_inst2.pdf. Please note that MARS Light is only instance-based¹, while MARS Full is planned to be fully instance-oriented.

5.1.1. MARS Light Architecture



5.1.2. MARS Full Architecture (planned)

¹Similar to OOP, where “object-based” means a weaker form of “object-oriented”, the term “instance-based” means that the *strategy* brick layer need not be fully modularized according to the IOP principles, but the *worker* brick layer already is.



5.2. Documentation of the Symlink Trees

The `/mars/` symlink tree is serving the following purposes, all at the same time:

1. For **communication** between cluster nodes, see sections 3.2 and 3.3. This communication is even the *only* communication between cluster nodes (apart from the *contents* of transaction logfiles and sync data).
2. **Internal interface** between the kernel module and the userspace tool `marsadm`.
3. **Internal persistent repository** which keeps state information between reboots (also in case of node crashes). It is even the *only* place where state information is kept. There is no other place like `/etc/drbd.conf`.



Because of its internal character, its representation and semantics may change at any time without notice (e.g. via an *internal* upgrade procedure between major releases). It is *not* an external interface to the outer world. Don't build anything on it.

However, knowledge of the symlink tree is useful for advanced sysadmins, for **human inspection** and for **debugging**. And, of course, for developers.

As an “official” interface from outside, only the `marsadm` command should be used.

5.2.1. Documentation of the MARS Light Symlink Tree

5.3. MARS Worker Bricks

5.4. MARS Strategy Bricks

5.5. The MARS Brick Infrastructure Layer

5.6. The Generic Brick Infrastructure Layer

5.7. The Generic Object and Aspect Infrastructure

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