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Nutanix Certified Professional - Business Continuity (NCP-BC) 7.5 Sample Questions (Q65-Q70):

NEW QUESTION # 65
An administrator executes a Recovery Plan for a set of high-performance VMs configured with SR-IOV network adapters. The VMs failover successfully to the Recovery Cluster.
What is the state of these VMs immediately after the planned failover completes?

- A. The failover fails during the validation phase because SR-IOV VMs cannot be protected.
- B. The VMs are powered on, but SR-IOV is disabled and replaced with a standard virtio-net adapter.
- C. The VMs are powered on, and SR-IOV is active.
- D. The VMs are recovered in a powered-off state, and the SR-IOV profile is removed.

Answer: B

Explanation:
Single Root I/O Virtualization (SR-IOV) allows a virtual machine to bypass the hypervisor ' s virtual switch and communicate directly with a physical network adapter ' s virtual functions. This is commonly used for high-performance applications that require extremely low latency and high throughput. However, SR-IOV creates a " hard " dependency between the virtual machine and the specific physical hardware (NIC) of the host it is running on.
Disaster Recovery involves moving a VM to an entirely different cluster, which likely has different physical network adapters or a different SR-IOV configuration. Nutanix Disaster Recovery orchestration is designed to ensure that VMs can always boot at the recovery site, even if specialized hardware resources are unavailable.

For VMs configured with SR-IOV, the recovery process includes a built-in fallback mechanism. During failover, the system will recover the VM and power it on, but it will disable the SR-IOV attachment. To ensure connectivity, it automatically adds or falls back to a standard virtio-net virtual adapter. This allows the VM to have network access immediately, though at a potentially lower performance level. The administrator must then manually re-configure SR-IOV at the recovery site if the local hardware supports it. This design prioritizes service availability (powering on and communicating) over specialized hardware performance during a disaster recovery event.

NEW QUESTION # 66
A third-party backup solution is configured to use Nutanix application-consistent snapshots. Backups are failing for several Windows VMs, although crash-consistent snapshots succeed.
What is the most likely cause of the failure?

- A. NGT is not installed or not communicating.
- B. Replication traffic encryption is disabled.
- C. Bandwidth throttling is configured too low.
- D. The protection policy uses asynchronous replication.

Answer: A

Explanation:
Nutanix supports two main types of snapshots: crash-consistent and application-consistent. A crash-consistent snapshot is taken at the storage layer without any awareness of the guest OS state; it is equivalent to pulling the power plug on a server. An application-consistent snapshot is more complex because it requires the Nutanix cluster to " quiesce " the applications (such as SQL Server or Exchange) inside the guest OS, flushing pending writes to disk to ensure data integrity.
To perform this quiescence on Windows VMs, the Nutanix cluster must communicate with the Windows Volume Shadow Copy Service (VSS). This communication is handled exclusively by Nutanix Guest Tools (NGT). If NGT is not installed on the VM, or if the NGT agent is not running/communicating with the cluster, the system cannot trigger the VSS hardware provider. In this situation, any request for an " application- consistent " snapshot from a third-party backup solution will fail because the cluster lacks the necessary hooks into the guest OS. However, a " crash-consistent " snapshot will still succeed because it does not require any guest-level interaction. Therefore, when app-consistent backups fail but crash-consistent ones succeed, the most likely root cause is a missing or broken NGT installation on the affected virtual machines.

NEW QUESTION # 67
How does Nutanix Disaster Recovery automatically handle Container Mapping if a storage container with the same name does not exist at the recovery Nutanix cluster?

- A. The initial replication fails and generates a critical alert requiring manual mapping in Prism Central.
- B. The recovery points replicate to a random storage container at the recovery Nutanix cluster.
- C. The system automatically creates a new Storage Container with the same name on the remote site.
- D. The data is temporarily kept in the SSD tier of the remote site pending intervention.

Answer: C

Explanation:
Storage Container mapping is a fundamental requirement for successful replication between Nutanix clusters, as it defines where the replicated recovery point data will reside on the destination cluster. In the early versions of Nutanix Disaster Recovery, administrators had to manually map source containers to destination containers to ensure the replication stream had a valid landing zone. However, to simplify the deployment of BCDR solutions and reduce manual configuration errors, modern Nutanix Disaster Recovery behavior has been enhanced. If the system detects that a VM is protected but no manual container mapping has been established in Prism Central, it will proactively check the recovery site for a container with the same name as the source. If that container does not exist, the orchestrator will automatically create a new storage container with the identical name on the remote cluster to allow replication to proceed without interruption. This automation ensures that " out-of-the-box " protection policies can function immediately even if the recovery site hasn ' t been fully pre-provisioned with storage structures. This behavior prevents replication from failing due to minor administrative oversights and maintains the integrity of the data protection schedule.

NEW QUESTION # 68
An administrator needs to provide the QA team with a VM state from four days ago to test an older browser version. However, the

current production VM contains new application code and security patches that must not be deleted or overwritten. Which restore operation should the administrator perform to meet this requirement?

- A. Disk-level Attach from Snapshot
- B. In-place Restore (Revert)
- C. Out-of-place Restore (Clone)
- D. Self-Service Restore (SSR)

Answer: D

Explanation:
Nutanix offers several ways to recover data, ranging from full VM reverts to granular file-level access. In this scenario, the key requirement is to access historical data (from four days ago) without modifying or destroying the current production VM ' s state. Self-Service Restore (SSR) is the most efficient and least disruptive method to achieve this. SSR, which requires Nutanix Guest Tools (NGT) to be installed, allows an administrator or user to mount a historical snapshot disk directly to the existing VM as a new, temporary volume. This allows the QA team to browse the file system of the " four-day-old " state and copy the specific older browser version they need while the production application continues to run undisturbed with its new code and patches. An " In-place Restore " (Option C) would be disastrous here because it would roll back the entire VM, overwriting the new patches. A " Clone " (Option D) would work but is less efficient as it consumes additional vCPU, RAM, and full storage overhead for an entirely new VM. SSR provides the surgical precision needed for file-level testing while maintaining the integrity of the live production environment.

NEW QUESTION # 69
An organization is finalizing its Disaster Recovery (DR) plan. The primary objective is to balance cost- efficiency with a target RTO of under 15 minutes. Data currently resides in Object Storage, but the team is debating between a Zero Compute approach and a Pilot Light approach. Why would a Pilot Light infrastructure be selected over a Zero Compute model despite the higher " Moderate " cost?

- A. Faster recovery due to metadata and cluster already existing.
- B. Lowest cost option available for long-term idle infrastructure.
- C. Only model that allows for a " Power-On " recovery trigger.
- D. Eliminates the need for any Object Storage (S3/Blob) costs.

Answer: A

Explanation:
When designing disaster recovery to a cloud environment (such as NC2 on AWS or Azure), organizations must choose a compute model that aligns with their Recovery Time Objective (RTO). The " Zero Compute " model is the most cost-efficient because it stores only the data (snapshots) in low-cost Object Storage (S3 or Blob) and does not maintain a running cluster. However, the RTO for Zero Compute is high because, in a disaster, the organization must first deploy a new Nutanix cluster, configure it, and then begin the process of hydrating data from the Object Storage.
In contrast, the " Pilot Light " model involves keeping a minimal, active Nutanix cluster (e.g., 3 nodes) running at the recovery site. While this carries a moderate ongoing cost, it significantly reduces the RTO.
Because the cluster already exists, the management plane (Prism Central), the storage containers, and all metadata are already active. When a failover is triggered, the system only needs to power on the VMs or perform a small amount of data hydration. This allows the organization to meet aggressive RTO targets of under 15 minutes, which is generally impossible with the Zero Compute model. Pilot Light provides the " ready-to-go " infrastructure needed for mission-critical applications that cannot afford the multiple hours required to provision a fresh cluster from scratch during an emergency.

NEW QUESTION # 70
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