Securing Mobile CPSs against Stealthy Attacks
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http://cs.txstate.edu/~mg65/mcps

Motivation:
– Mobile Cyber-Physical Systems (Mobile CPSs) will be pervasively integrated into our physical world
– How to ensure the security and safety of Mobile CPSs?

Challenges:
– Reliance on wireless technology
  • Easy to jam and interfere with
– Complexity with real-time, energy and mobility constraints
  • Widens the malicious opportunities
– Attacks are not “random noise”, but are well orchestrated
  • Studies that focus on random noise and disturbance do not apply

Scope of work:
– Identifying stealthy attacks
– Developing defense mechanisms

Methodology: Identifying Stealthy Attacks

- Markov Decision Process
  – State of the system
  – Transitions

- Offense strategy
  – Aims to evolve the system into “bad” states (Z)
  – Pays a price when attacks
  – Gains a reward when inflicts damage
  – Identifies policies that maximize the cumulative rewards

- Exact Policy Iteration
  – Optimal policies can be obtained
  – Value determination: expected cost-to-go values are computed
  – Policy improvement: a better policy is generated

- The curse of dimensionality:
  – Large state space makes it computationally infeasible to obtain exact solutions [Bellman]

- Approximate Policy Iteration
  – Relies on Monte Carlo simulations
  – Characterizes states based on a set of feature
  – Uses a parametric cost-to-go approximation for the value function [Bertsekas]

Stuck in Traffic (Sit) Attacks on Intelligent Transportation Systems

- The setup
  – Decision points reflect loads on segments
  – Drivers make informed decisions
  – Attackers aims to cause congestion

- Scenarios
  – Traffic optimization

- Damage
  – Degree of imbalance

- Cost
  – Number of vehicles affected

http://arxiv.org/abs/1210.5454

Stealthy Attacks on Target Tracking Applications

- The setup
  – Target moves randomly
  – Agent seeks to find the target
  – Attacker aims to hinder tracking

- Scenarios
  – Search and rescue
  – Border control

- Damage
  – Distance between the agent and the target
  – Negative if target is found

- Cost
  – Different values for control and measurement signals

Collaborators: George Alia (UCF), Vu Nguyen (Texas State), Janiece Kelly (Texas State) and Seth Richter (LeTourneau)

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