Machine Learning Enhanced Real-Time Intrusion

Detection Using Timing Information





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- 1. Motivation
- 2. Detection Analyses
- 3. RT Performance of ML Library
- 4. Application and Experiments
- 5. Future Work and Ackownledgement

Motivation

- 1. Rising cyber attacks toward Internet-of-Thing(IoT) systems / embedded systems
- 2. Insufficient traditional intrusion detection methods
- 3. Migration of ML from cloud to edge

Past Work

- 1. Timing analysis
- 2. Physical model verification
- 3. Packet encryption
- 4. Communication frequency

Our Work

1. Separate intrusion detection system and target system

2. ML model for state verification

3. Real-time suitability optimization of ML library



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Two Analyses

- Timing Analysis
 - Execution time of certain paths in program code
 - Communication delay between the detector and controller (Timestamps of communication in packets under monitoring)
- Third Party Model Verification
 - Internal Physical Telemetries
 - External Physical Telemetries

Packet arrival	Detection Algorithm			
timeliness validity	: function DETECT_ANOMAL	Y(socket)		
(detector	2: $Data = read(socket);$			
blockingly wait	$I_{dtc} = gettimeof aay();$ if $Data \le 0$ then		PARAMETERS OF THE DETECTION ALGORITHM	
exclude packet	b: return True;	> packet not received	Symbol	Description
buffering delay	$T_{tgt}, T_{ctrl}[N], PHY$	$[i_{in}, PHY_{ex}] = parse(Data);$	N	vector size of execution time for different code snippets on the target control code
	return True:	▷ data packet not received in time	D_{comm}	deadline of communication delay
For a strength of the strength	else if $\exists i, T_{ctrl}[i] > 1$	$WCET[i], 0 \le i < N, i \in \mathbb{Z}$ the	WCET[N]	worst-case execution time vector
	. return True;	▷ execution time over bound	TH_{ML}	ML model verification threshold
Execution time	2: else		socket	controller socket file descriptor
validity	MSR_{in}, MSR_o	ut] =	Data	streaming data from controller
	$select_telemetru(PHY_{in},$	PHY _{er})	T_{dtc}	the data reception timestamp on the detector
	$EXP_{out} = ML_{out}$	$Model(MSR_{in})$	T_{tgt}	the transmission timestamp on the controller
	If $ EAP_{out} - M $	$ SR_{out} > I H_{ML}$ then	$T_{ctrl}[N]$	execution time vector on target control system
ML model	else	> ML venification failed	PHY_{in}	internal physical telemetries
informa	Resturn False:	> No anomaly	PHY_{ex}	external physical telemetries
inference 🧪	end if	P No anomary	MSR_{in}	physical telemetries selected as measured inputs
comparison): end if		MSRout	physical telemetries selected as measured outputs
•	end if		EXP_{out}	inference output of ML model
	2: end function			

Fusion of Analyses

• Assign weights for thresholds of different detection metrics

• Fuse to obtain entire detection threshold

• Counter stealthy attack

Increased Isolation

1. Between application space and OS kernel space (execution time information managed by kernel)

2. Between controller and detector

3. Between internal and external physical state data sources

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Edge Computing



- Real-Time features of ML API on edge
 - Shorter average execution time
 - Tighter worst case execution time (WCET)

- Large streaming data inputs
- Data privacy concerns
- Lower latencies

Real-time Optimization for ML Library

- 1. Insufficient real-time predictability of keras and original Caffe libraries
- 2. Reducible detection delay
 - promptness of detection
 - compatibility with high sampling rate of control system

ML Libraries

1. Keras (Tensorflow backended)

- Interpreter-based language
- No real-time control of dynamic memory management

2. Caffe

- Native C/C++ language
- Real-time control of dynamic memory management

3. Enhanced Caffe

- Remove third party library invocation functions in source code
- Remove multi-core support



Caffe

RT Performance Comparison

- Keras vs. Original Caffe
- Average execution time
- 4:1
- Stadard deviation of execution time
- less varying : much more varying
- **RT-Enhanced Caffe vs. original Caffe** Average execution time
 - 1: 6
- Standard deviation of execution time
- 1:25 (comparison between the minimum values)



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Application for Intrusion Detection

- 1. Solar power system
- 2. Power output estimation
- 3. Inverter controlled by DSP (embedded system)
- 4. Inverter is emulated by Pi3 B



Model Preparation

- Model training
 - on HPC system with GPU support
 - Keras tensorflow backended
 - model converted into caffe compatible format
- Model inference
 - on raspberry Pi

RT predictability; embedded system; power efficiency; ML infrastructure support

Experiment of Intrusion Detection System



Experiment Configuration

- 2kw maximum model output magnitude; percentage of prediction error threshold: 1%, 5%, 10%.
- 10ms valid execution time; percentage of execution time deviation threshold: 0.1%,1%,10%
- Communication delay upper bounded 2.7ms
- 2500 samples of timing and ML prediction each experiment run
- 80% samples with intrusion(20% samples with timing deviation less than the smallest timing threshold), 20% without intrusion

Results

1. Inverter ouptout power deviation threshold larger,

FP smaller

FN larger

accuracy decreases

2. Timing threshold larger,

FP smaller

FN larger

accuracy decreases

3. False positive and false negative rate vary in opposite directions



(WCET(ms), ML Model Threshold (watt))

Conclusion

1. We enhanced prior intrusion detection based on timing analysis via ML model verification.

2. We conducted experiments to demonstrate its effectiveness based on practical industrial data.

3. We investigated the trade-off between FP and FN rates when selecting the detection thresholds of WCET and ML model output.

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Future Work

- Timing analysis based cyber protection
 - Network stack
 - User library for open source programs
 - Runtime library
 - OS Kernel
 - Parametric timing analysis
 - Safe-mode transition

Acknowledgement

This work was funded in part by NSF grants 1329780, 1525609, and 1813004.

Thank you!