

I DPID It My Way!

A Covert Timing Channel in Software-Defined Networks

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Abstract—Software-defined networking is considered a promising new paradigm, enabling more reliable and formally verifiable communication networks. However, this paper shows that the separation of the control plane from the data plane, which lies at the heart of Software-Defined Networks (SDNs), can be exploited for covert channels based on SDN Teleportation, even when the data planes are physically disconnected.

This paper describes the theoretical model and design of our covert timing channel based on SDN Teleportation. We implement our covert channel using a popular SDN switch, Open vSwitch, and a popular SDN controller, ONOS. Our evaluation of the prototype shows that even under load at the controller, throughput rates of 20 bits per second are possible, with a communication accuracy of approximately 90%. We also discuss techniques to increase the throughput further.

1. Introduction

In the recent years computer networks have undergone a transformation to overcome *ossification* [1]. Existing communication protocols and architectures were unable to meet the increasingly stringent requirements, e.g., in terms of performance but also dependability, of growing networks such as data center networks and wide area networks [2].

One of the answers to the *ossification* problem is what is now known as Software-Defined Networks (SDN) which is the separation (and consolidation) of the network control plane from the data plane. SDNs promises innovation, reduced cost and better manageability [3].

As of today, we witness an increasing interest in SDN not only in academia and the industry but also by governments [4]. Several open-source SDN projects have gained wide-spread adoption by the community, e.g., Open vSwitch and OpenDayLight are a part of the Linux foundation. Hardware vendors are also adopting the SDN paradigm and shipping software programmable network cards [5].

While the literature has demonstrated well how an SDN can overcome the shortcomings of traditional networks and while SDNs are rapidly gaining traction, researchers have also identified new security challenges they introduce. For example, Hong et al. [6], and Dhawan et al. [7] identified ways for an attacker to spoof the controller’s view of the network topology. Jero et al. [8] identified a weakness in the way controllers bind *network identifiers* allowing an attacker to conduct a man-in-the-middle attack.

Those papers show that attacks on the controller can easily occur from the data plane. The assumption that the data plane can be compromised, e.g., via trojans, or software exploits, is not far fetched. For example, Thimmaraju et al. [9] demonstrated the simplicity of compromising the data plane of an SDN-based cloud system.

The SDN controller may also be exploited for *teleportation*, e.g., malicious switches or hosts can communicate via the control plane and circumvent data plane security mechanisms [10] to exfiltrate sensitive information. Teleportation can also be exploited by physically disconnected switches, e.g., switches in different geographic locations. More importantly, teleportation is inherent to an SDN. Among the teleportation techniques identified [10], out-of-band forwarding, flow reconfiguration and switch identification, only out-of-band forwarding has been explored in the literature [10]. Switch identification and flow reconfiguration were described as a *Rendezvous Protocol*.

Hence in this paper, we go beyond the initial intention of switch identification teleportation by describing how it can also be used for covert communication: malicious switches can transfer a 2048 byte *RSA private key file* in ~ 13 minutes. In particular, we design, develop and evaluate a time-based covert channel using the switch identification teleportation. **Our Contributions:** We describe the state machine of switch identification and model it in terms of time delays. We then design a covert timing channel using our model. We prototype our design and evaluate its performance and accuracy. Finally, our study of the OpenFlow handshake leads us to the observation that it is currently insecure. The vulnerability received *CVE-2018-1000155* and mitigations have been announced.

Novelty and Related Work: To the best of our knowledge, this is the first paper that describes a covert timing channel in an SDN, and OpenFlow-based network in particular. We are only aware of one other paper dealing with covert channels in SDN, which is however very different in nature: Hu et al. [11] proposed to use SDN to improve the detection of storage covert channels that use the TCP flags for covert communication. More generally, the study of covert channels dates back to the 80’s when Simmons [12] introduced the “Prisoners Problem” and the *subliminal channel*. Network based covert channels in local area networks were introduced by Girling [13], wherein a covert channel based on the inter frame delay was proposed. Handel et al. [14] conducted an extensive study on viable covert channels within the OSI

3.1. Single Bit Transfer

From the message sequence pattern in Fig. 1, switch s_2 can infer a binary value of 1 if it gets disconnected, and a binary value of 0 if it is able to connect, thereby received one bit of data. We can precisely describe the states and transitions to transfer one bit value as state machines for the sender and receiver resp. Additionally, we can precisely describe a time-based model to transfer one bit value that can be leveraged to design a channel to transfer multiple bits. In the following we describe the state transition model and time model to transfer one bit. Following that, we describe our algorithms to transfer multiple bits.

3.1.1. State Transition Model. The state transition model for switch identification involves a *sender* and *receiver*. As the names imply, the sender sends a binary bit value by either connecting to the controller or not. Similarly, the receiver receives a binary bit value by detecting whether its OpenFlow connection to the controller is allowed or denied.

In our model, we make the following assumptions. We assume that the sender and receiver use an a priori agreed upon DPID (one that is not used in the network), a time to connect to the same OpenFlow controller and a time interval Δ . Δ , is the total time the sender and receiver use to send and receive resp. a bit value. The sender and receiver have synchronized their clocks. We discuss synchronization further in Sec. 4.1. The receiver in particular, is always able to connect to the controller a short δ_{offset} time after the sender. The controller, behaves according to outcome i (see Switch Identification Teleportation). The receiver infers a binary bit value of 1, if its OpenFlow connection is denied, i.e., the sender connected to the controller before the receiver. The receiver infers a binary bit value of 0, if its OpenFlow connection is accepted, i.e., the sender did not connect to the controller.

The sending and receiving of bit information can be described in more detail by defining a set of states and transitions for the sender and receiver resp., as shown in Fig. 2. The sender *starts* data transmission with an agreed upon DPID, by entering into the *Idle* state. To send a 0, it simply remains in the *Idle* state. To send a 1, it transitions to the *OpenFlow-established* state via the *Set-Controller* transition. *Set-Controller* involves initializing internal objects, e.g., *rconn* and *vconn* data structures in Open vSwitch, in order to initiate a transport (e.g., TCP) connection to the controller at a specific IP and port address. It also involves establishing the TCP and OpenFlow connection with the controller. Once the OpenFlow connection is established, the sender waits for a timeout δ_{ws} , to move into the *Timeout-reached* state. From there, the sender enters into the *OpenFlow-disconnected* state by tearing down the TCP and OpenFlow connection, and deleting its controller information. From thereon, the sender completes a bit transfer by entering back into the *Idle* state. The sender's state diagram is depicted in Fig. 2a.

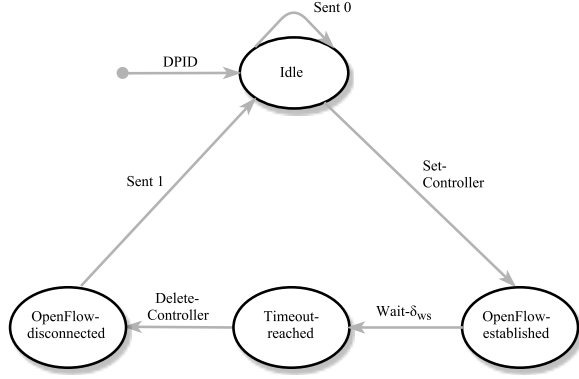
The receiver also starts with the same DPID to enter into the *Idle* state. Unlike the sender, the receiver must always at-

tempt to connect to the controller to receive a 0 or a 1. It waits for δ_{offset} time to enter the *Offset-reached* state before it sets the controller to enter into the *OpenFlow-established* state, similar to the sender. If the receiver's OpenFlow connection is denied, it will enter into the *OpenFlow-disconnected* state resulting in its OpenFlow and transport connection being terminated. If the receiver's OpenFlow connection is accepted, it will enter into the *OpenFlow-accepted* state resulting in its OpenFlow connection being sustained. Regardless of the outcome, the receiver waits δ_{delay} time, thereby transitioning to the *Reached-check-status-timeout* state. From there, the receiver checks the OpenFlow connection status. It enters the *Got-1* state if it was disconnected, i.e., it got a 1. It enters the *Got-0* state if it was accepted, i.e., it got a 0. From there on the receiver deletes its controller information, resulting in the OpenFlow and transport connection being torn down if it is still present. Depending on the value of Δ , there may still be time left, hence the receiver waits δ_{wr} , till the end of time interval, to enter the *Timeout-reached* state. It then completes the reception by moving back into the *Idle* state. The state diagram for the receiver is shown in Fig. 2b.

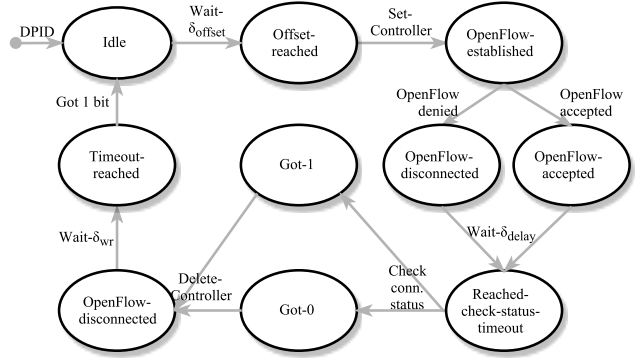
3.1.2. Transition Delays. To leverage switch identification as a covert timing channel we must first establish the time it takes for the sender to send a 1—as sending a 0 requires the sender to remain in the *Idle* state—and the receiver to receive a bit value. We define a *time interval* Δ , as the time the sender and receiver use to send and receive resp. a binary bit value.

Δ comprises of the several state transitions described for the sender and receiver (Sec. 3.1.1). We can construct a time-based model by considering the transitions as delays or timeouts for the sender and receiver that can be used to analyze the performance of our covert channel. In the following we define the various delays and timeouts for the sender and receiver state transitions.

- 1) δ_s : The time the sender takes to send a binary bit value.
- 2) δ_r : The time the receiver takes to receive a binary bit value.
- 3) δ_{sc} : The time to transition from the *Idle* state to the *OpenFlow-established* state.
- 4) δ_{dc} : The time to move from the *OpenFlow-established* state to *OpenFlow-disconnected* state.
- 5) δ_{offset} : A timeout value the receiver waits before it sets the controller.
- 6) $\delta_{of-deny}$: The time to move from *OpenFlow-established* to *OpenFlow-disconnected* when the connection is denied.
- 7) δ_{delay} : A timeout value the receiver waits before it checks the OpenFlow connection status.
- 8) $\delta_{chk-conn}$: The time the receiver takes to determine a 0 or 1 by checking the OpenFlow connection status.
- 9) $\delta_{ws} = \Delta - \delta_s$: A timeout value the sender waits before moving from the *OpenFlow-established* state to *OpenFlow-disconnected*.



(a) Sender



(b) Receiver

Figure 2: State diagram for the sender and receiver to send/receive one binary value.

- 10) $\delta_{wr} = \Delta - \delta_r$: A timeout value the receiver waits before moving from the *OpenFlow-disconnected* state to the *Idle* state.

Using the above definitions, we can now compute the time to send and receive a 0 or 1. The total time to send a 0 or 1 is shown in Eq. 1. As we can see, it takes more time to send a 1 compared to a 0. In Eq. 2, we can see the time it takes to receive a 0 or a 1. In particular, the different delay is $\delta_{of-deny}$ for the 1. For the sender and receiver to operate correctly, we require the inequality shown in Eq. 3 to hold, i.e., the time interval Δ must not be less than the total time to send or receive a binary bit value.

Additionally, for the receiver to correctly detect a 0 and 1, we require the inequalities as shown in Eq. 4 and 5 to hold. The former equation states that δ_{offset} must be greater than the time it takes for the sender to enter the *OF-established* state. This is to ensure that the receiver does not connect before the sender when the sender wants to send a 1. The latter equation states that the minimum amount of time it can wait before checking the OpenFlow connection status is 0, and the maximum time it can wait depends on the time interval, the time elapsed so far, and the time for the remaining transitions to complete. The δ_{delay} gives the receiver the flexibility of waiting for some amount of time before checking the status of the OpenFlow connection. For example, checking the connection status at $\Delta/2$, i.e., at the middle of the time interval, may be better than checking it at $\Delta/4$. Hence, the receiver can set δ_{delay} such that, the OpenFlow connection status is checked at a point where the connection is most stable.

$$\delta_s = \begin{cases} 0, & \text{to send 0} \\ \delta_{sc} + \delta_{dc}, & \text{to send 1} \end{cases} \quad (1)$$

$$\delta_r = \begin{cases} \delta_{offset} + \delta_{sc} + \delta_{delay} \\ + \delta_{chk-conn} + \delta_{dc}, & \text{to get 0} \\ \delta_{offset} + \delta_{sc} + \delta_{of-deny} \\ + \delta_{delay} + \delta_{chk-conn} + \delta_{dc}, & \text{to get 1} \end{cases} \quad (2)$$

$$\delta_s \leq \delta_r \leq \Delta \quad (3)$$

$$\delta_{offset} \geq \delta_{sc} \quad (4)$$

$$0 \leq \delta_{delay} \leq \Delta - (\delta_{offset} + \delta_{sc} + \delta_{of-deny} + \delta_{chk-conn} + \delta_{dc}) \quad (5)$$

3.2. From One Bit to Multiple Bits

Until now, we have described how the sender can transmit only a single bit value to the receiver. To receive the single bit value, the sender and receiver need to be synchronized, i.e., the sender and receiver must know the exact time at which the time interval Δ begins and ends. To this end, we assume the sender and receiver synchronize their clocks using the same network time protocol (NTP) time server. Furthermore, we assume the sender and receiver agree upon specific times at which they will initiate their covert communication.

In order to be useful, a covert channel should provide a sender with the ability to transmit several kilobytes of data, e.g., an RSA private key file. Accordingly, in the following, we extend our discussion from a single bit transmission to multiple bits. First, the sender and receiver must agree upon an encoding/decoding scheme, e.g., ASCII. Second, they must also agree upon a method to signal the *start* and *end* of a message. To do so, we use a frame-based transmission method. In particular, the sender encodes a message M into *frames* F , of length Fl , and transmits the frames. The receiver, decodes each frame received to obtain the sent message.

For *simplicity*, we consider a frame with at least one *SoF* (Start of Frame) bit, and at least seven *data* bits (e.g., ASCII characters can be represented in 7 bits). The *SoF* bit is used by the sender to signal the receiver that a frame transmission begins which is followed by data bits. We assume that the *SoF* bit is a binary 1, and if the receiver gets this value at the

Algorithm 1 To send binary data as frames.

Require: Message M , Frame-length Fl , Frames F , Time-interval Δ , Start-time t

```

1: initialize(sender)
2: for frame  $\in F$  do
3:   set-controller ▷ Send SoF bit
4:   Wait  $\delta_{ws}$ 
5:   for bit  $\in$  frame do
6:     if (bit==0) then
7:       delete-controller ▷ Send 0
8:     else
9:       set-controller ▷ Send 1
10:    Wait  $\delta_{ws}$ 
11:    delete-controller

```

agreed upon time and time interval, it will begin receiving data bits. The data bits can be 0 or 1 depending on how the message is encoded. To indicate the end of a message, the sender sends a frame with all the data bits as 0. When the receiver receives such a frame, it will terminate execution. The above steps are specified as algorithms for the sender and receiver in Alg. 1 and 2 resp.

The sender’s algorithm, accepts several inputs, e.g., M is the message to be transmitted, Fl is the frame length, e.g., 8, F is the list of frames that are to be sent, Δ is the time interval, and t is the transmission start-time. The input values for the receiver are the same frame length, time interval and start-time as the sender.

For every frame to be sent, the sender first sends a *SoF* bit for that frame by connecting to the controller. Similarly the receiver waits for δ_{offset} time before attempting to receive the *SoF* bit. If its connection is denied, it will begin receiving data bits. After sending the *SoF* bit, the sender sends data bits: if sending a 0, it disconnects from the controller, if sending a 1, it connects to the controller. It then waits till the end of the timing interval before sending the next data bit. The receiver detects the data bits in a frame by connecting to the controller, and waiting for δ_{delay} time before checking whether its OpenFlow connection was allowed or not. If the connection was accepted, it will append a 0 to the data bits received in the frame, otherwise it will append a 1. The receiver then deletes the controller, and then waits δ_{wr} , i.e., till the end of the time interval before connecting to the controller again.

Once the sender has sent the data bits of a frame, it will wait δ_{ws} time, i.e., for the next time interval to send the next frame. The receiver detects the end of a message when it has received a frame with all the data bits zeroed, thereby terminating the while loop at the receiver. The receiver can then decode the binary data to reveal the message sent.

4. Design and Performance Challenges

Our covert channel design requires us to overcome several non-trivial challenges. Hence, we discuss the most important challenges that affects our design in this section before transitioning to our implementation. We also cast light on factors that affect the performance of our design.

Algorithm 2 To receive binary data as frames.

Require: Frame-length Fl , Time-interval Δ , Start-time t

```

1: initialize(receiver)
2: while End of message not received do
3:   Wait  $\delta_{offset}$ 
4:   set-controller ▷ Receive SoF bit
5:   Wait  $\delta_{delay}$ 
6:   Check OpenFlow connection state
7:   if OpenFlow denied then ▷ Got SoF bit
8:     Wait  $\delta_{wr}$ 
9:     for bit  $\in Fl$  do
10:      set-controller ▷ Get data bit
11:      Wait  $\delta_{delay}$ 
12:      Check OpenFlow connection state
13:      if OpenFlow accepted then
14:        frame += "0" ▷ Got 0
15:      else frame += "1" ▷ Got 1
16:      delete-controller
17:      Wait  $\delta_{wr}$ 
18:      if frame == "0000000" then
19:        End of message received
20:        Break ▷ Terminate reception
21:      else
22:        M+ = frame ▷ Append frame to message

```

4.1. Synchronization

One of the main problems in designing a covert timing channel is synchronization. Lack of synchronization can lead to the receiver obtaining inaccurate information, thereby reducing the accuracy of the channel. The sender and receiver must share a reference clock to ensure that the the algorithms start at the same time. To this end, we use NTP (as it easily available for today’s popular operating systems) and the same NTP server to synchronize the clocks of the sender and receiver to achieve at least millisecond accuracy [21]. Since the sender and receiver clocks can slowly drift apart their clocks must be periodically synchronized with the same NTP server.

When the clocks are synchronized, the *SoF* bit(s) in each frame sent synchronizes the receiver with the sender enabling the receiver to obtain the data bits. During the transmission of a frame, we introduce the δ_{ws} and δ_{wr} times for the sender and receiver resp. at the end of a time interval for synchronization across time intervals in a frame. Furthermore, between frames the sender and receiver can synchronize again by waiting, for example for the next second. This *inter frame delay* adds another layer of synchronization to enable the sender and receiver to send and receive resp. the *SoF* bit(s) accurately.

4.2. Determining the Time Interval Δ and Delays

The time interval in which the sender and receiver send and receive a bit leads to the achievable throughput of the channel. As the time interval reduces, the probability of an error occurring increases, e.g., the receiver may check the connection status before receiving the TCP FIN from the controller. Furthermore, system and network artefacts can

non-deterministically influence the state transitions resulting in errors. Hence, the challenge here is to determine a time interval as small as possible within an acceptable level of accuracy ($\geq 95\%$). We empirically identify suitable time intervals in Sec. 5 based on our prototype implementation. However, in the real-world, the channel would have to start with a programmed value, e.g., 1s, and later be negotiated.

Recall Sec. 3.1.2, there are several delays involved in our timing channel. The delays for one network system, may not be applicable elsewhere. Delays such δ_{sc} , δ_{dc} , $\delta_{of-deny}$, and $\delta_{chk-conn}$, depend on the system and network conditions. Moreover, they are not under the control of the sender/receiver. The timeouts δ_{offset} and δ_{delay} although bounded (see Eq. 4 and 5 resp.) can be tuned by the receiver. Hence, we evaluate 3 different δ_{delay} values in Sec. 5.

4.3. Frame-based Transmission

Our design uses a frame-based method to transfer data from the sender to the receiver. The smallest frame size we consider is 8 bits long: 1 *SoF* bit and 7 data bits. The size of this frame can change, e.g., we can send 14 or 28 data bits as well. Sending more data bits in a frame reduces the overhead of sending the *SoF* bit. We can also increase the number of *SoF* bits to ensure the receiver can get the data bits. However, increasing the number of bits in a frame increases the probability of errors within a frame. We do not consider error correction in our design although it can be introduced, e.g., using Hamming codes. However, we do include a minimal set of error detections at the receiver which we describe next.

Receiver misses the start bit of the frame: Several reasons can affect the receiver from missing the *SoF* bit of a frame. In such cases the receiver simply remains idle for the remainder of the time that is necessary to transmit an entire frame.

End of Transmission: For simplicity, the sender indicates the end of transmission via a special *EoM* (End of Message) frame. This design choice comes with a couple of challenges for the receiver to correctly terminate. First, if the receiver misses the *SoF* bit of the *EoM* frame, then it will continue to expect to receive frames. To address this problem, we define a threshold number of consecutive frames, e.g., 5, the receiver does not receive beyond which the receiver terminates reception. Second, the receiver can incorrectly detect a 1 as a 0 due to synchronization issues for example. As a result, the receiver may detect the *EoM* prematurely and stop receiving data even though the sender continues to send data. We cannot address this case as it is a limitation of our design to not include the length of the message to be received.

4.4. Influence of the Controller

The OpenFlow controller that is used to covertly communicate is beyond the control of the sender and receiver. Hence, the accuracy and performance of our channel is limited by the controller that operates the OpenFlow network.

Load on the Controller: Typically, there are more switches connected to the controller than just the sender and the receiver of the covert channel. If the communication between the benign switches and the controller is frequent and voluminous, the sender and receiver will experience non-deterministic delays in connecting/disconnecting (δ_{sc} , δ_{dc} and $\delta_{of-deny}$) to the controller, thereby reducing the performance (throughput and accuracy) of the channel.

Controller Architecture: The system and software architecture of the controller also influences our design. For example, the controller could be single threaded or multi-threaded. The former can lead to long delays, whereas the latter can lead to non-determinism due to the scheduler.

Path to the Controller: Network paths not under the control of the sender and receiver can influence the performance of our channel. For example, buffers in switches can be filled up by other network packets resulting in packet loss and hence errors in the received bits.

5. Evaluation

To obtain deeper insights and validate our expectations of our covert channel, we prototyped our design using Open vSwitch [22] and ONOS [23]. Furthermore, we designed a set of experiments based on the challenges described in the previous section to characterize the performance of our channel. We begin with a brief description of our implementation, and then describe the experiments.

5.1. Implementation

We used Open vSwitch (OvS) as our sender and receiver OpenFlow switches. We only modified the (OpenFlow) connection handling of OvS so that after it disconnects from the controller, it waits for 4 seconds to reconnect. To set/delete controller information, and configure the DPID, we used the *ovs-vsctl* tool that ships with OvS. We then implemented the sender and receiver algorithms (Alg. 1 and 2) as python scripts. In doing so, we traded performance for *simplicity* which we consider acceptable for the sake of prototyping and evaluation. Our implementation is only meant to demonstrate the *feasibility* of our attack.

We synchronized the system clocks of the sender and receiver using our university’s NTP time server. To encode and decode the messages, we used the ASCII scheme. We implemented an adaptive *inter-frame delay* synchronization scheme in which the sender sends a frame only at the start of the next second.

5.2. Setup and Methodology

Our evaluation setup comprised of three (sender, receiver and controller) Dell PowerEdge 2950 servers with 4 core Intel(R) Xeon(TM) CPU 3.73GHz processors and 16 GB of RAM each. The sender and receiver were directly connected to the controller. For OpenFlow load generation, we used a fourth server running directly connected to the controller.

All these servers used dedicated ports to connect to a management switch that was used for orchestration from a fifth server to conduct the evaluation. All systems ran Ubuntu 14.04.5 LTS. For the sender and receiver, we used Open vSwitch 2.7. For the controller, we used ONOS 1.10.2.

Based on our covert timing channel design the objectives of the evaluation are the following. First, we want to establish time intervals that achieve high accuracy and throughput. Second, we want to determine the influence the frame length has on the accuracy, e.g., do shorter frames have fewer errors than longer frames? Third, we want to measure the influence of δ_{delay} on the accuracy and throughput of our channel e.g., is there a δ_{delay} value for which the time interval can be smaller? Finally, we want to measure the accuracy of our channel when there is load on the controller.

The general methodology we undertake is the following. The controller runs ONOS with the default applications activated. We program the sender and receiver with a specific start time t , time interval Δ , offset $\delta_{offset} = 5\text{ ms}$, check the connection status at $\Delta/2\text{ ms}$ and frame length Fl . The sender then sends a 64 byte message M_s and the receiver receives a message M_r . We then restart ONOS and OvS, and clean up the OvS database before we repeat the measurement. We collect ten such measurements for the configured values. We measure accuracy as the similarity between M_r and M_s using the *edit distance* or *Levenshtein distance* [24].

For load on the controller, we use OFCProbe [25] as our OpenFlow topology and packet generator. We configure OFCProbe to emulate 20 switches that trigger Packet-Ins to the controller following a Poisson distribution ($\lambda=1$). After OFCProbe has started the Packet-in generation, we wait for one minute before we start the sender and receiver, to avoid any warm-up effects from OFCProbe and ONOS.

5.3. Experiments

Following the aforementioned methodology, we now describe the experiments and their results.

Effect of Timing Interval Δ : We set the frame length $Fl = 7$, and measure the accuracy for time intervals from 30 ms up to 100 ms . The results are shown in Fig. 3.

The results depict that our channel can achieve nearly 100% accuracy for time intervals greater than 60 ms when there is no load on the controller. For $\Delta = 60\text{ ms}$, we have a throughput of approximately 16.67 bps . What we can also see is that as the time interval increases the accuracy increases, which is what we expected. Another distinct observation is that for the values configured, our channel cannot operate below 40 ms because the receiver gets the *EoM* prematurely, (it detects only 0 in the data bits).

Effect of Frame Length Fl : To measure the influence of the frame length on the accuracy we chose the following values: 7, 14 and 28. Note that these values represent the number of data bits in the frame, i.e., 1, 2, and 4 ASCII characters resp. We use only one *SoF* bit in the frame. We repeat the measurements for time intervals from $30\text{--}100\text{ ms}$. The results from this experiment are depicted in Fig. 3.

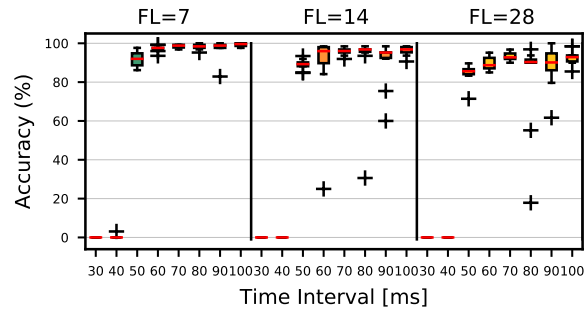


Figure 3: Channel accuracy for time intervals $30\text{--}100\text{ ms}$, and frame lengths 7, 14 and 28 when $\delta_{offset} = 5\text{ ms}$, OpenFlow status is checked at $\Delta/2$, and there is no load on the controller.

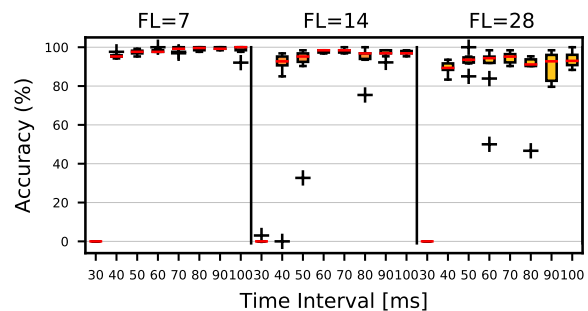


Figure 4: Channel accuracy for time intervals $30\text{--}100\text{ ms}$, and frame lengths 7, 14 and 28 when $\delta_{offset} = 5\text{ ms}$, OpenFlow status is checked at $2\Delta/3$, and there is no load on the controller.

Indeed, the frame lengths we used show us that as the frame length increases the accuracy drops. Longer frame lengths result in fewer frames but more data per frame being sent. Hence, if the receiver misses the *SoF* bit for $Fl = 14$, it misses twice as many characters compared to $Fl = 7$. Moreover, the chance of incorrect bit detection (bit-flips) increases with larger frames. We analyzed the errors and observed that indeed as the frame length increases, the number of bit-flips increase, and the number of missed *SoF* bits also increase. To address the problem of missing the start bit we can introduce redundant *SoF* bits.

Effect of δ_{delay} in Checking Connection Status: We now investigate how δ_{delay} influences the throughput and accuracy of our channel. Recall from Sec. 3.1.2 that this value is the time the receiver waits before it checks the status of the OpenFlow connection. Until now, we checked the connection status at $\Delta/2$. Hence, in this experiment we check the connection status at $2\Delta/3$ and $\Delta/3$ for frame lengths 7, 14 and 28, and time intervals $30\text{--}100\text{ ms}$. The results for $2\Delta/3$ and $\Delta/3$ are shown in Fig. 4 and 5 resp.

When we check the status at $2\Delta/3$, the 40 ms time interval operates at nearly 100% accuracy. Moreover, the accuracy for this δ_{delay} value performs better compared to

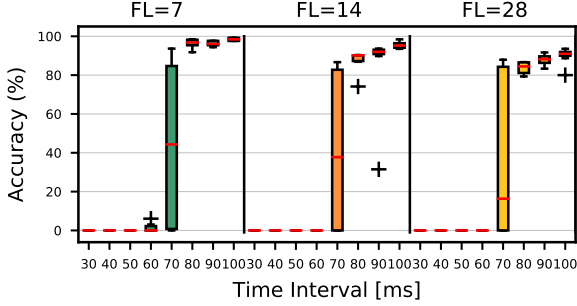


Figure 5: Channel accuracy for time intervals 30-100 ms , and frame lengths 7, 14 and 28 when $\delta_{offset} = 5ms$, OpenFlow status is checked at $\Delta/3$, and there is no load on the controller.

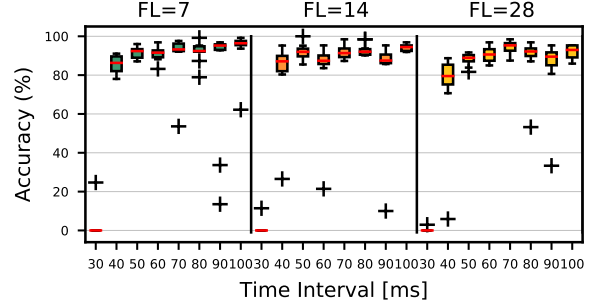


Figure 7: Channel accuracy for time intervals 30-100 ms , and frame lengths 7, 14 and 28 when $\delta_{offset} = 5ms$, OpenFlow status is checked at $2\Delta/3$, and there is load on the controller.

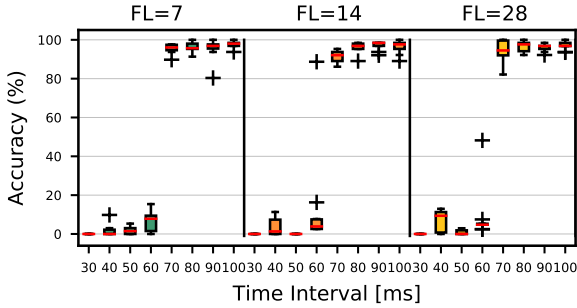


Figure 6: Channel accuracy for time intervals 30-100 ms , and frame lengths 7, 14 and 28 when $\delta_{offset} = 5ms$, OpenFlow status is checked at $\Delta/2$, and there is load on the controller.

our baseline value of $\Delta/2$. When we check the status at $\Delta/3$, we observe a negative influence on the channel, i.e., time intervals 50-70 ms are not effective. In particular, we note that the 70 ms time interval is the operational edge when δ_{delay} is at $\Delta/3$. The reason for these marked changes is the following: The time at which the receiver checks the OpenFlow connection status is crucial. Done too soon, it is likely to detect a zero, and done too late, it is likely to detect a one.

Based on our design, detecting a 1 as a 0 reduces the accuracy more than detecting a 0 as a 1: missing the *SoF* bit (1) can lead to missing the entire frame, and detecting zeros for all the data bits results in the *EoM*. Combining the two can drastically bring down the accuracy which is evidenced when we check the status at $\Delta/3$.

Effect of Message Length $|M|$: To ensure that our channel can sustain longer messages, we measured the accuracy of sending 512 and 1024 byte messages with and without load. The accuracy in each case was very close to the 64 byte message, hence we chose not to show the results here.

Effect of Load on the Controller: Having determined time intervals, frame lengths and δ_{delay} values with close to 100 % accuracy, we compare them with measurements when the controller is under load, as real OpenFlow network can

operate with more than two switches. Fig. 6 and 7 illustrate the results from this experiment.

Naturally, load on the controller reduces the accuracy of our channel. Other switches trigger events at the controller which introduces queuing and processing delays for the sender's and receiver's messages. This introduces errors for time intervals that were previously highly accurate, e.g., 60 ms and checking the OpenFlow connection at $\Delta/2$ (Fig. 6) drops to roughly 10% when the controller is under load. Although there is a drop in the accuracy when we check the connection at $2\Delta/3$ (Fig. 7), the smaller time intervals, e.g., 50 ms can still operate at or above 90% accuracy.

6. Discussion

Our evaluation demonstrated that switch identification teleportation can be a highly accurate channel for low throughput covert communication in our setup. We also showed that it depends on several factors, e.g., Δ , δ_{delay} , and the system and network conditions. Nonetheless, techniques to detect teleportation in general, and a covert timing channel such as the one presented in this paper are crucial for networks with high security demands. Hence, we briefly discuss detection possibilities. We also describe some limitations and possible improvements for our design and implementation.

Detection and Mitigation: To the best of our knowledge, firewalls and intrusion detection systems do not monitor the OpenFlow sessions. Even if they are, detecting teleportation attacks are non-trivial as they follow the *normal* pattern of (encrypted) OpenFlow sessions. Preventing switch identification teleportation is exacerbated by the fundamental requirement that switches need to uniquely identify themselves to the controller, and that the controller must allow only a single DPID in the network. However, the attack can be deterred if OpenFlow connections are secured via the following hardened authentication scheme: unique TLS certificates for switches, white-list of switch DPIDs at controllers [26] which also includes the switches' respective public-key certificate identifier, and lastly a controller mechanism that verifies the DPID announced in the OpenFlow handshake is over the TLS connection with the associated (DPID) certificate.

Limitations and Improvements: Indeed, our prototype implementation achieves throughput rates in the order of tens of bits per second. However, it is reasonable to assume that the throughput can be increased by, implementing our algorithms in OvS which is programmed in ‘C’, or using another controller. Consequently, the delays, e.g., δ_{sc} , will be reduced as the response time to events will be faster, e.g., we will not have to rely on *vsctl* and *ovsdb* to set/delete the controller. A novel approach to increase the throughput which we have not measured is for the sender and receiver to initiate several concurrent connections to the controller using unique DPIDs for each connection. In this manner, the sender can send as many bits as connections are made, thereby increasing the throughput by the number of connections. Our channel also comes with some system and network level limitations that are difficult to overcome, e.g., time to establish a TCP connection, packet loss along the path to the controller, etc. Furthermore, our design is for uni-directional communication and does not include error correction. A channel from the receiver back to the sender where the receiver acknowledges, e.g., every frame, can boost the accuracy of the channel.

7. Conclusions

In this paper, we described the design, implementation and evaluation of a novel covert timing channel based on the switch identification teleportation technique. Our prototype implementation of our design can achieve throughput rates of up-to 20 bits per second, with an accuracy of approximately 90% even when there is load at the controller. This means that a 2048 byte RSA private key file can be transferred in nearly 13 minutes. Although our *proof-of-concept* implementation is a low bandwidth channel, we discussed techniques to increase the throughput.

Software-defined networks have become the standard way of doing networking in large data centers, and service provider networks are also moving towards such an architecture and paradigm. With Advanced Persistent Threats (APTs) becoming an increasing problem, covert channels such as the one described in this paper become more relevant, e.g., private keys bought in the black market are used for phishing and malware campaigns. Hence, we must design and develop mechanisms to detect and prevent teleportation attacks that gives APTs a way to covertly communicate or exfiltrate data to a command and control center.

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