

DRAFT: Trust Framework Operation in Autonomous Marine Communications Environments

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Abstract. This paper presents a Trust Management Framework (TMF) for Marine Autonomous Networks. We present a comparative study on the operation and performance of such trust frameworks between a typical terrestrial and the harsh underwater communications environment, examining the scaling factors involved (periodicity, physical spacing, etc.) in comparing and contrasting these environments. We demonstrate the need for a different approach towards metric selection and trust-timing in such constrained networks.

Keywords: ad-hoc, MANET, trust, marine, underwater, acoustic

1 Introduction

As mobile ad-hoc networks (MANETs) grow beyond the terrestrial arena, their operation and the protocols designed around them must be reviewed to assess their suitability and optimality in different communications environments to ensure their continued security, reliability, and performance.

Trust Management Frameworks (TMFs) provide information to assist the estimation of future states and operations of nodes within networks. This information is used to optimize the performance of a system of systems in the face of malicious, selfish, or defective behaviour by one or more nodes within such a system. Previous research has established the advantages of implementing distributed TMFs in terrestrial, 802.11 based mobile ad-hoc networks (MANETs), particularly in terms of preventing selfish operation in constrained collaborative systems [Li and Singhal, 2007], and maintaining throughput in the presence of malicious actors [Buechegger and Le Boudec, 2002]

Current TMFs generally use a single type of observed action to derive trust metrics, i.e. successfully forwarded packets. These historical observations then

inform future decisions of individual nodes, for example, the selection of a forward router with the lowest previous Packet Loss Rate (PLR) [Li et al., 2007].

Recent work has demonstrated use of a number of metrics to form a 'vector of trust. In the case of Multi-parameter trust framework for MANETs (MTFM)[Guo, 2012], these metrics related to inter-node communications. This vectorized trust allows a system to detect anomalous behaviour and identify the tactics being used to undermine or subvert trust. To date this work has been limited to terrestrial, RF based, communications networks. As autonomous underwater vehicles (AUVs) become more capable, and economical, they are being used in many defence, commercial and environmental applications. These applications are tending towards utilising independent collective behaviour of teams or fleets of these platforms [Caiti, 2011] With this use being increasingly independent of classical command and control structures, the accurate and timely establishment of mutual and distributed communications trust between nodes within such fleets is essential for the reliability and stability of such systems, and to the secure integration of such systems into larger management systems-of-systems. As such, the application of Trust methods developed in the terrestrial MANET space must be re-appraised for application within the challenging underwater communications channel.

The paper is laid out as follows. In Section 2 we discuss Trust and Trust Management Frameworks, defining our terminology and reviewing the justifications for the use and development of Trust Management Frameworks. In Section 3, we review selected features of the underwater communications channel, highlighting particular challenges and differentials against terrestrial equivalents. In Section 4, we review the results presented in [Guo et al., 2011], including a critique of the use of Fuzzy Sets and Gray Theory and a discussion on differences in experimental configuration when transitioning from terrestrial radio to the marine space. We establish the initial parameters for simulation and set out a series of experiments to establish commonality between trust establishment in terrestrial and marine networks, characterising the communications and physical configuration with respect to the application and channel characteristics. In Section 5, we present our findings in trust establishment in this optimal network, pointing out the differences in metric selection and their impact on trust assessment stability.

The contributions to the field of this paper are:

- A Trust Management Framework applicable to Underwater MANETs
- A study on the comparative operation and performance between terrestrial and underwater MANETs using TMFs.
- A review of metric suitability for Trust Management Frameworks in marine environments, informing future metric selection for experimenters and theorists.

2 Trust and Trust Management Frameworks

2.1 Trust in MANETs

In human trust relationships it is recognised that there can be several perspectives of Trust for example organizational, sociological, interpersonal, psycholog-

Needs to be converted to prose

ical and neurological [Lee and See, 2004]. Trust is the level of confidence one agent has in another to perform a given action on request or in an emergent context.

Similarly, trust in the autonomous or semi-autonomous realm is the ability of a system to establish and maintain confidence in itself or another systems operations. Managing this trust can be used to predict and reason on the future interactions between entities in a system, such as an autonomous mobile ad-hoc network (MANET).

The distributed and dynamic nature of MANETs mean that it is difficult to maintain a trusted third party (TTP) or evidence based trust system such as Certificate Authorities or using Public Key Infrastructures (PKI). Therefore, a distributed, collaborative system must be applied to these networks. Such trust management frameworks (TMFs), where nodes in a network share information about the trust state of the network, with an aim to detecting, identifying, and mitigating the impacts of malicious actors, are an active area of ongoing research.

2.2 Current Trust Management Frameworks

Various models and algorithms for describing trust and developing trust management in distributed systems, P2P communities or wireless networks have been considered. Taking some examples;

- *The Objective Trust Management Framework* takes a Bayesian approach and introduces the idea of applying a Beta function to changes in the per-link Packet Loss Rate (PLR) over time as an encapsulation method, combining “Trust” and “Confidence of Assessment” into a single value [Li et al., 2007]. OTMF however does not appropriately combat multi-node-collusion in the network [Cho et al., 2011].
- *Trust-based Secure Routing* [Moe et al., 2008] demonstrated an extension to Dynamic Source Routing (DSR), incorporating a Hidden Markov Model of the wider ad-hoc network, reducing the efficacy of Byzantine attacks, particularly black-hole attacks but, along with many more TMFs surveyed in [Cho et al., 2011], falls under the same limitation of focusing on single metric observation (PLR).
- *CONFIDANT*; [Buechegger and Le Boudec, 2002] presented an approach using a probabilistic estimation of normal observations, generating a posterior probability distribution of node forwarding behaviours, similar to OTMF. They also introduced a greedy topology weighting scheme that internally weighted incoming trust assessments based on historical experience of the reporter.
- *Fuzzy Trust-Based Filtering*; [Luo et al., 2008] presented a method using Fuzzy Inference to cope with imperfect or malicious recommendation based on a probabilistic estimation of performance using conditional similarity to classify performance using overlapping Fuzzy Set Membership functions to collaboratively filter reputations across a network.

OTMF, CONFIDANT, and Fuzzy Trust-Based Filtering can be generalised as single-value probabilistic estimation, based around a Bayesian idea of taking a binary input state and generating an idealised Beta Distribution (1) of the future states of that input generated through an expectation value based on interactions (2).

$$\text{beta}(p|\alpha, \beta) = \frac{\Gamma(\alpha + \beta)}{\Gamma(\alpha)\Gamma(\beta)} p^{\alpha-1}, \text{ where } 0 \leq p \leq 1; \alpha, \beta > 0 \quad (1)$$

$$E(p) = \frac{\alpha}{\alpha + \beta} \quad (2)$$

Where α and β represent the number of successful and unsuccessful interactions respectively.

These single metric TMFs provide malicious actors with a significant advantage if their activity is undetectable by that one assessed metric, especially if the attacker knows the metric in advance.

There are situations where the observed metrics will include significant noise involved with complicated interdependencies between the environment and the system under observation; and those observations themselves occur at irregular, sparse, intervals. In such cases, conventional approaches such as Bayesian prior probability estimation do not produce trust values that fairly reflect the underlying metrics, as they require a-priori assumption that the trust value under exploration has a known or expected distribution (Beta), that that distribution is monomodal, and that the input metrics are binary discernible. These assumptions are required to scale and classify resultant trust values to a stable assessment range (usually $[0, 1]$) [Liu, 2006]. In scenarios with variable, sparse, noisy metrics, estimating the distribution is difficult to accomplish off-line in advance. Further, the binary requirement of Bayesian-style modelling requires internal discriminating logic, which discards useful information from a multi-node perspective, and generating a phase transition area where a proportion of negative or malicious behaviour does not impact the assessed trust observations of other nodes, but still impacts system performance [Mundinger and Boudec, 2008].

Finally, there is no accounting for the context in which the assessment is taking place; while OTMF does include topological information, it does not take account of environmental factors that may be inducing poor performance.

Grey Theory counters this by performing cohort based normalisation of metrics at runtime. This creates a more stable contextual assessment of trust, providing an “extent” of potential trust values with respect to other observed nodes in that interval rather, while still maintaining the ability to reduce trust values down to a stable assessment range for decision support without having to characterise every environment entered into. This presents a stark difference between the Grey System and Probabilistic approaches. In Grey, assessments are relative in nature even in fairly operating networks. Nodes will generally receive middle-range trust assessments if there are no malicious actors as there is no-one else “bad” to compete against. Future work will investigate the stability of GRA under multi-node collusion

Table 1 provides a qualatative summary of the differences in use and application between Fuzzy, Probabilistic and Grey Systems of managing uncertainty.

Table 1: Comparison between selected methods of characterising uncertainty, adapted from [Ng, 1994] [Liu, 2006] [Wang et al., 2006] [Guo et al., 2011]

	Fuzzy Math	Probabilistic Estimation	Grey Systems
Objects	Cognitive Uncertainty	Distribution Refinement	Poor Information
Set Style	Fuzzy Sets	Cantor Sets	Grey Hazy Sets
Methodology	Discerning Affiliation	Probability Distribution	Information Coverage
Processes	Marginal Sampling	Frequency Distribution	Sequence Generation
Data Requirement	Known Membership	Beta Distribution	Any Distribution
Emphasis	Extension	Intension	Intension
Objective	Cognitive Expression	Stabilisation	Realism
Characteristics	Experience	Large Samples	Small Samples

2.3 Grey Theory Operation

The objective of operating a TMF is to increase the confidence in, and efficiency of, a system by reducing the amount of undetectable negative operations an attacker can perform. This “set” of potential attacks can be described as a “threat surface”. In the case where the attacker can subvert the TMF, the metric under assessment by that TMF does not cover the threat mounted by the attacker. In turn, this causes a super-linearly negative effect in the efficiency of the network as the TMF is assumed to have reduced the threat surface when in fact it has only made it more advantageous to attack a different aspect of the networks operation. An example of such a behaviour would be the case in a TMF focused on PLR where an attacker selectively delays packets going through it, reducing the over all throughput of one or more virtual network routes. Such behaviour would not be detected by the TMF.

Guo[Guo, 2012] demonstrated the ability of Grey Relational Analysis (GRA)[Zuo, 1995] to normalize and operationally combine disparate traits of a communications link such as instantaneous throughput, received signal strength, etc. into a single comparable value, a Grey Relational Coefficient, or a “trust vector”.

In the case of the terrestrial communications network used in [Guo, 2012], the observed metric set $X = \{x_1, \dots, x_M\}$ representing the measurements taken by each node of its neighbours at least interval, is defined as

$$X = \{\text{packet loss rate, signal strength, data rate, delay, throughput}\} \quad (3)$$

The trust vector is then given as

$$\theta_{k,j}^t = \frac{\min_k |a_{k,j}^t - g_j^t| + \rho \max_k |a_{k,j}^t - g_j^t|}{|a_{k,j}^t - g_j^t| + \rho \max_k |a_{k,j}^t - g_j^t|} \quad (4)$$

$$\phi_{k,j}^t = \frac{\min_k |a_{k,j}^t - b_j^t| + \rho \max_k |a_{k,j}^t - b_j^t|}{|a_{k,j}^t - b_j^t| + \rho \max_k |a_{k,j}^t - b_j^t|} \quad (5)$$

$$[\theta_k^t, \phi_k^t] = [(\theta_{k,0}^t, \dots, \theta_{k,M}^t), (\phi_{k,0}^t, \dots, \phi_{k,M}^t)] \quad (6)$$

where $a_{k,j}^t$ is the value of a observed metric x_j for a given node k at time t , ρ is a distinguishing coefficient normally set to 0.5, g and b are respectively the 'good' and 'bad' reference metric sequences from $\{a_{k,j}^t, k = 1, 2 \dots K\}$, e.g. $g_j = \max_k(a_{k,j}^t)$, $b_j = \min_k(a_{k,j}^t)$ (where each metric is selected to be monotonically increasingly positive for trust assessment, e.g. throughput). θ and ϕ are then scaled to $[0, 1]$ using the mapping $y = 1.5x - 0.5$. The vector natures of $[\theta_k^t, \phi_k^t]$ allow per-metric weighting before generating a single trust assessment, and also allows the identification and classification of untrustworthy agents. These weighted $[\theta, \phi]$ values are then condensed into a single trust value by

$$T_k^t = \frac{1}{1 + \frac{(\phi_k^t)^2}{(\theta_k^t)^2}} \quad (7)$$

GRA, combined with a fuzzy whiteization model (8), and a topology-aware weighting scheme(9) ¹ provide capability to both detect the existence of a malicious agent within the network, and to classify what trust metrics that attacker is manipulating.

There are three classes of topological trust relationship; Direct, Recommendation, and Indirect. To take the example of a node n_i monitoring the trust of another, target, node, n_j ; the Direct relationship is simply the trust assessment based on n_i 's own observations and experience of n_j 's behaviour. In the Recommendation case, another node, n_k , which shares direct relationships with both n_i and n_j , gives it's opinion on the trustworthiness of n_j to n_i . The Indirect case is similar to the recommendation case, except that the recommender n_k , does not have a (current) direct link with the target n_j but that has a direct link with the observer node, n_i .

These relationships give us node sets, N_R and N_I containing the nodes that have recommendation or indirect, relationships to the observing node respectively.

$$\begin{aligned} f_1(x) &= -x + 1 \\ f_2(x) &= \begin{cases} 2x & \text{if } x \leq 0.5 \\ -2x + 2 & \text{if } x > 0.5 \end{cases} \\ f_3(x) &= x \end{aligned} \quad (8)$$

¹ similar to that employed in CONFIDANT

$$\begin{aligned}
T_{i,j}^{net} = & \frac{1}{2} \cdot \max_s \{f_s(T_{i,j})\} T_{i,j} && \text{Direct Trust} \\
& + \frac{|N_R|}{2|N_R| + |N_I|} \sum_{n \in N_R} \max_s \{f_s(T_{i,n})\} T_{i,n} && \text{Recommendation Trust} \\
& + \frac{|N_I|}{2|N_R| + |N_I|} \sum_{n \in N_I} \max_s \{f_s(T_{i,n})\} T_{i,n} && \text{Indirect Trust}
\end{aligned} \tag{9}$$

3 Marine Acoustic Networks

The key challenges of underwater acoustic communications are centred around the impact of slow and differential propagation of energy (RF, Optical, Acoustic) through water, and it's interfaces with the seabed / air. The resultant challenges include; long delays due to propagation, significant inter-symbol interference and Doppler spreading, fast and slow fading due to environmental effects (aquatic flora/fauna; surface weather), carrier-frequency dependent signal attenuation, multipath caused by the medium interfaces at the surface and seabed, variations in propagation speed due to depth dependant effects (salinity, temperature, pressure, gaseous concentrations and bubbling), and subsequent refractive spreading and lensing due to that same propagation variation [Partan et al., 2006].

The attenuation that occurs in an underwater acoustic channel over a distance d for a signal about frequency f in linear and dB forms respectively is given by

$$A(d, f) = A_0 d^k a(f)^d \tag{10}$$

$$10 \log A(d, f) / A_0 = k \cdot 10 \log d + d \cdot 10 \log a(f) \tag{11}$$

where A_0 is a unit-normalising constant, k is a spreading factor (commonly taken as 1.5), and $a(f)$ is the absorption coefficient, expressed empirically using Thorp's formula (12) from [Stojanovic, 2007]

$$10 \log a(f) = 0.11 \cdot \frac{f^2}{1 + f^2} + 44 \cdot \frac{f^2}{4100 + f^2} + 2.75 \times 10^{-4} f^2 + 0.003 \tag{12}$$

Thus, the multi-path channel transfer function can be described by

$$H(d, f) = \sum_{p=0}^{P-1} h(p) = \sum_{p=0}^{P-1} \Gamma_p / \sqrt{A(d_p, f)} e^{-j2\pi f \tau_p} \tag{13}$$

where $d = d_0$ is the minimal path length between the transmitter and receiver, $d_p, p = \{1, \dots, P-1\}$ are the secondary path lengths, Γ_p models additional losses incurred on each path such as reflection losses at the surface interface, and

$\tau_p = d_p/c$ is the delay time ($c = 1500ms^{-1}$ is the nominal speed of sound underwater).

This combination of refractive lensing and the multipath nature of the medium result in supposedly “line of sight” propagation being extremely unreliable for estimating distances to targets, as the first arriving beam has as the very least bent in the medium, and commonly has bounced between the surface/seabed before arriving at a receiver. Further, this affect is usually anisotropic with differential depths between transmitter and receiver, meaning that any variation in depth across a channel, greatly impacts the characteristics of that channel.

Comparing (10) with the RF Free-Space Path Loss model (14), while both are frequency and distance dependant;

$$A_{rf}(d, f) \approx \left(\frac{4\pi f}{c} \right)^2 \text{ where } c \approx 3 \times 10^8 m/s \quad (14)$$

3.1 Trust in Marine Networks

Justify Why Grey,
discuss current
uses and demand.
Relate back to
Section 2.1

In this subsection we establish the requirement for communications trust in acoustic marine networks, extending and expanding on the generic assessment given in 2.1

4 Initial System Model Characterisation

4.1 Scenarios

Four Mobility scenarios were used in [Guo et al., 2011] to explore the trust-behaviour, covering the majority of MANET operational requirements;

- All Nodes Static
- Central node performing a random walk with leaf-nodes static
- Leaf-nodes randomly walking with central node static
- All nodes randomly walking

The six nodes are arranged as per Fig. 1, such that each node is on average 100m from its neighbours. The use of six nodes and the particular layout enables the investigation of the three trust relationships based on minimum path topologies, such that the node generating the trust assessments, n_0 has Direct, Recommendation, and Indirect trust assessments available to it from itself, $[n_2, n_3]$, and $[n_4, n_5]$ respectively.

In all of the scenarios, each link from $n_i \rightarrow n_j$ sent 10 second bursts of Constant Bit Rate (CBR) style traffic.

Guo demonstrated that when compared against OTMF and Beta trust assessment, MTFM provided increased variation in trust assessment over time, providing more information about the nodes behaviour than simply the probabilistic nature of packet delivery. Guo also demonstrated that this MTFM valuation was stochastically stable for varying mobilities.

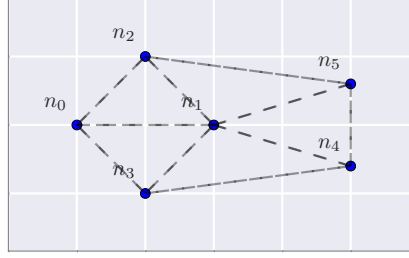


Fig. 1: Initial Scenario Topology, with nodes spaced an average of 100m apart

4.2 Simulation Background

Simulations were conducted using a Python based agent simulation framework based on SimPy[Müller and Vignaux, 2003], with a network stack built upon the AUVNetSim stack[Miquel and Montana, 2008], with transmission parameters (Table 2) taken from and validated against [Stojanovic, 2007] and [Stefanov and Stojanovic, 2011].

Given the differences in delay and propagation between RF and marine networks, it is natural that the same application rates (e.g. packet emission rates or throughput) cannot be equal. Therefore, before we can fairly assess the trust operation of a Underwater MANET, we first establish an equally operational zone of performance.

We define a methodology for establishing an comparative operating point in the marine environment that can account for the differences in communications environment while maintaining a comparable trust operation.

4.3 Scaling Considerations between Terrestrial and Underwater Environments

In this section we characterise the simulated communications environment, establishing an optimal packet emission rate for comparison against [Guo et al., 2011].

We establish a appropriate safe operating zone for marine communications by looking at the communications rate and physical distribution factors together across the four presented scenarios. From Table 2, the operating transmission range of acoustic is ≈ 6 times further than 802.11, indicating that a suitable operating environment will have an area $\approx \sqrt{6}$ times the area of the 802.11 case. Therefore, a reasonable experimental range would have an upper bound of performance around this scaling factor, where nodes are approximately 400m apart. We select throughput and end to end delay as the targeted aspects of the networks performance to optimise against. The raw results of these two metrics in the static scenario are shown in Fig. ???. We take the ratio of throughput per second of delay as a combined proxy for this optimisation. T/d , shown in Fig. ???.

Fig. ??? demonstrates that there is a severe drop off in performance in stable performance in increasing packet emission rates above 0.02, even though Fig. ??? on it's own would indicate an optimal zone in at a much higher rate. However,

Table 2: Comparison of system model constraints as applied between Terrestrial and Marine communications

Parameter	Unit	Terrestrial	Marine
Simulated Duration	s	300	36000
Simulated Area	km^2	0.7	Various
Transmission Range	km	0.25	1.5
Number of Nodes		6	6
Physical Layer		RF(802.11)	Acoustic
Propagation Speed	m/s	3×10^8	1490
Center Frequency	Hz	2.6×10^9	2×10^3
Bandwidth	Hz	22×10^6	10^3
MAC Type		CSMA/CA	CSMA/CA
Routing Protocol		DSDV	FBR
Mobility		Various	Various
Max Speed	ms^{-1}	5	2.4
Data Rate	bps	10^6	240
Burst Counts		10	1
Packet Size	bits	4096	9600
Destination Selection		Random	Random
Single Transmission Duration	s	10	32
Single Transmission Size	bits	10^7	9600

due to increased medium contention and queueing delays at these rates enter into the order of hours, which is unacceptable for many applications. These results indicate that the best area to continue operating in for a variety of node separations is at 0.015pps, and that a reasonable position scaling is from 100m to 400m, beyond which communication becomes increasingly unstable, especially in terms of end to end delay.

5 Trust

Having established a safe operating range for comparison, we proceed to repeat the scenarios presented in [Guo et al., 2011] in this simulated marine network.

The particular factors under discussion are the relative performance of MTFM against OTMF and Beta with respect to statistical stability across scenarios and in responsiveness to changing network behaviour. We establish a similar result set by initially tracking the resultant trust values established by MTFM in each of the four mobility scenarios. For simplicity, we are primarily concerned with the observational trust relationship between node 0 and node 1, i.e. n_0 's assessment of the trustworthiness of n_1 , or $T_{1,0}$. Some groups use a reverse notation for trust, whereby $T_{1,0}$ would represent the trustworthiness of n_1 according to n_0 ; however, given the subjective nature of trustworthiness, it is more relatable

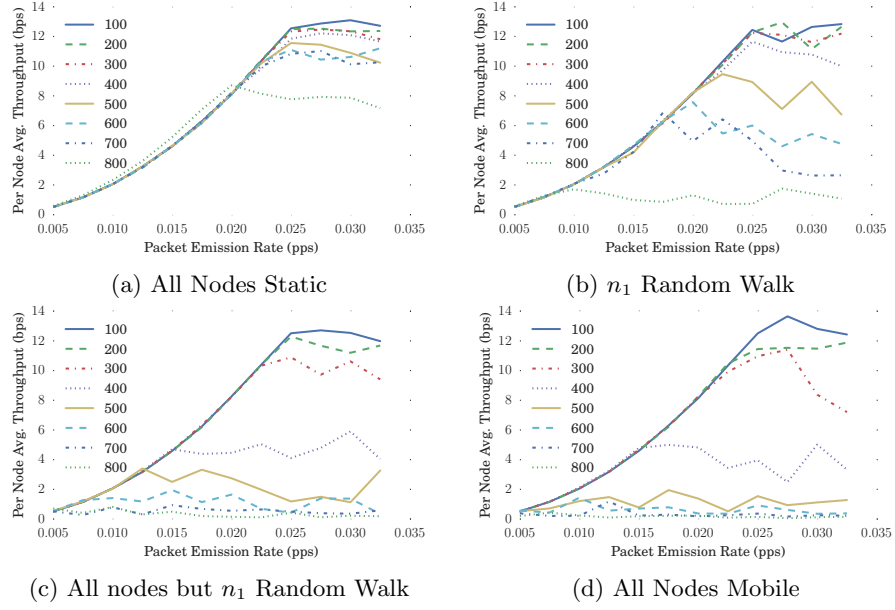


Fig. 2: Throughput Characteristics for varying node separations across increasing packet emission rates

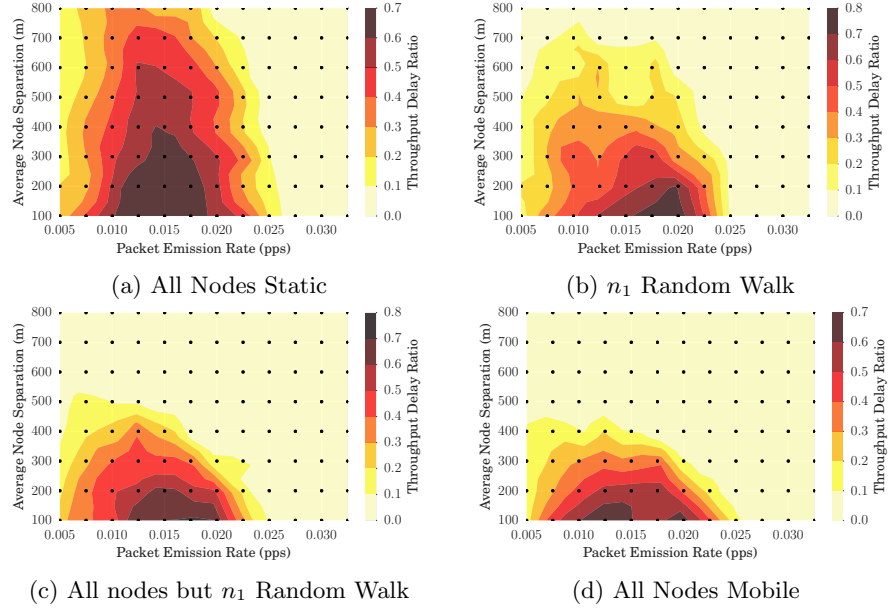


Fig. 3: Throughput Characteristics for varying node separations across increasing packet emission rates

to describe $T_{1,0}$ as “The Trustworthiness of n_1 from the perspective of n_0 , rather than an absolute statement on n_1 ’s trustworthiness. We are also concerned with the opinions of n_1 provided to n_0 by other nodes, where $T_{1,2}, T_{1,2}$ and $T_{1,2}, T_{1,2}$ denote the sets of recommendation and indirect trust assessments respectively. Also included are a set of aggregate assessments; $T_{1,\text{avg}}$, the flat average of direct trust assessments of n_1 , $T_{1,\text{Net}}$, an aggregate that weights assessments according to the network topology from (9), and $T_{1,\text{MTFM}}$, the final MTFM trust assessment value based on both network topology and whitenisation from (8).

From Fig. 5a, the generated trust values utilising the topology information ($T_{1,\text{Net}}, T_{1,\text{MTFM}}$) display a greatly decreased variation than those of the individual subjective observations.

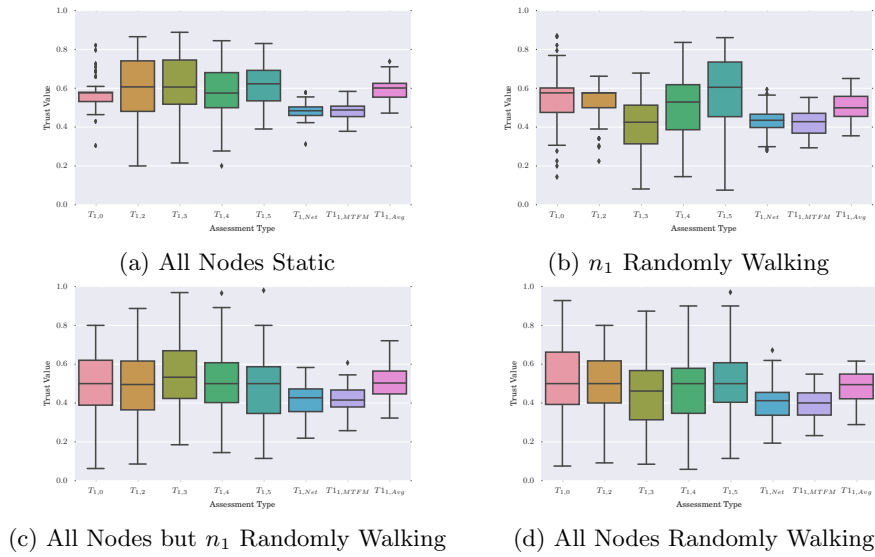


Fig. 4: MTFM Trust assessments for varying mobility options

5.1 Metric Selection

Initially, all the available metrics (transmitted and received throughput, delay, received signal strength, transmitted power, and packet loss rate) were utilised for Grey assessment. One danger with Multiple Metric based trust frameworks and particularly a dynamical system like Grey Theory, is that useless or invalid metrics are included (or indeed, excluded), as recognised by Liu [Liu and Lin, 2011].

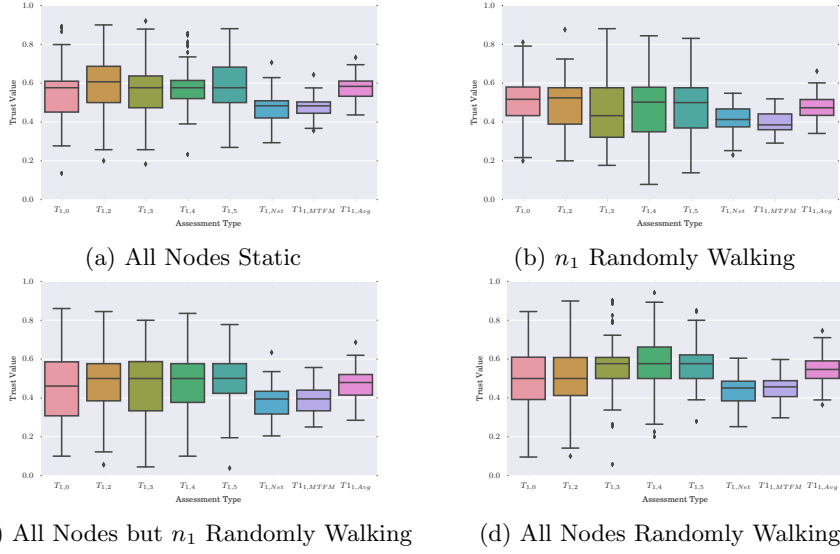


Fig. 5: MTFM Trust assessments for varying mobility options

5.2 Weight Generation

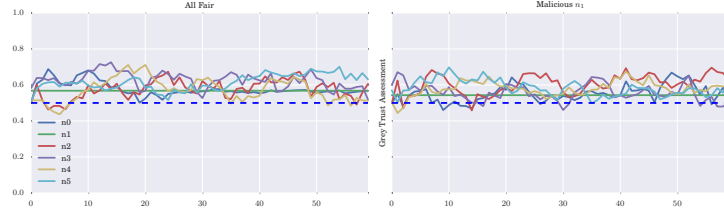
For an arbitrary metric weight vector H , where the metric m_j is emphasised as being twice as important as the other metrics, we form an initial weighting vector $H' = [1, 1, 1, 1, 2, 1]$ for $j = 4$ for example. We then scale that vector H' such that $\sum H = 1$ by $H = \frac{2H'}{\max H' \times \sum H'}$.

5.3 Comparison to OTMF and Beta

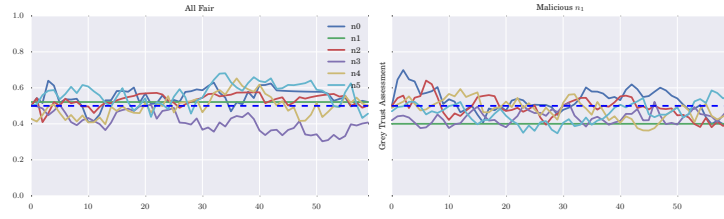
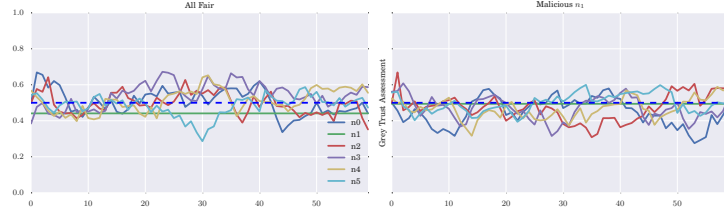
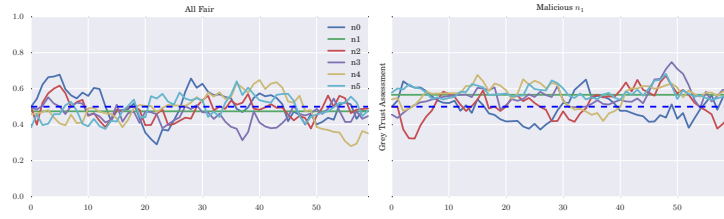
The same experiments were also performed utilising OTMF and Beta assessment as well as MTFM, providing like-for-like comparison of assessment at runtime.

It is important to note a distinction between the expectations of MTFM compared to other trust assessment frameworks; it is primarily concerned with the detection and identification of malicious or mistaken behaviours, and is relativistic in its operation. That is to say that under Grey Theory, agents are compared against the worst current performances across various metrics and graded against them. OTMF and Beta in comparison are absolutist in their approach, and do not factor in a comparative metric for assessment; in the Bayesian book, you are good or bad regardless of what everyone else is doing. This relativistic vs absolutist differential is particularly stark when comparing mobility models.

MTFM keeps a steady assessment that the node under assessment, n_1 , is behaving “OK” regardless of mobility model. However, the network itself is most under strain with full mobility, with the routing topology changing every few minutes, requiring route advertisements and request overheads that contend the already valuable channel.

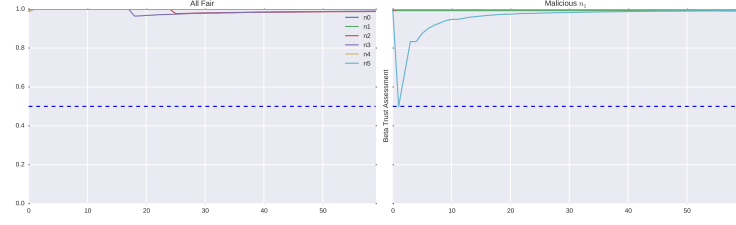


(a) All Nodes Static

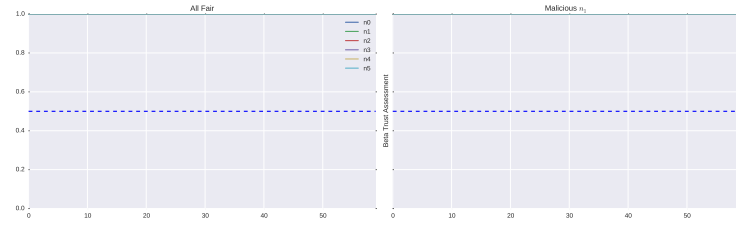
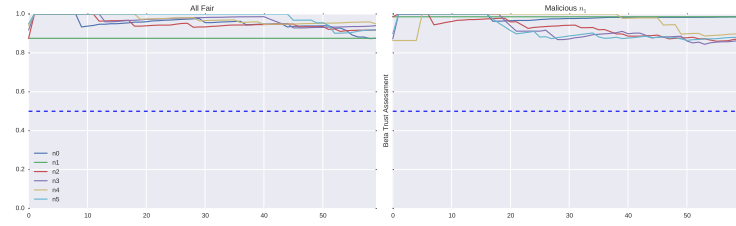
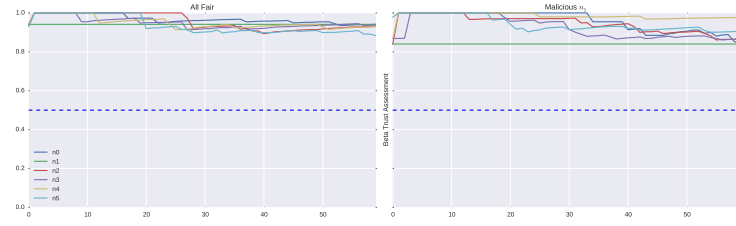
(b) n_1 Randomly Walking(c) All Nodes but n_1 Randomly Walking

(d) All Nodes Randomly Walking

Fig. 6: MTFM Trust time varying assessments for of n_1 varying mobility options



(a) All Nodes Static

(b) n_1 Randomly Walking(c) All Nodes but n_1 Randomly Walking

(d) All Nodes Randomly Walking

Fig. 7: Beta Trust time varying assessments for of n_1 varying mobility options

5.4 Comparison under malicious behaviour

Introducing a malicious actor into a trusted network with the aim to identifying the actor and the form of the malicious action is the driving force behind this work. Guo introduces a range of malicious actors, including modification of the packet loss rate of routing nodes and limiting throughput on a per-link basis as well as a selection of combined mis-behaviours.

In all cases, the malicious node is n_1 , the node that n_1 is “attacking” is n_0 , who is also the primary observer, e.g. the value of trust under assessment is $T_{0,1}$

– *Single Metric Misbehaviours*

- *Packet Loss Rate*: n_1 selectively denies n_0 's packets to reduce n_0 's apparent PLR from the perspective of the rest of the network.
- *Signal Strength*: n_1 increases its standard operating signal strength for all nodes *except* communications with n_0 .
- *Delay*: n_1 introduces artificial delays to its communications with n_0

Given that the established links are already heavily constrained, these heavy handed attacks simply cripple the network, an initi

6 Conclusions and Future Work

We have demonstrated that existing MANET Trust Management Frameworks cannot be directly applied to the contentious and dynamic underwater medium. With significant delays (order from seconds to hours), a fading, refractive medium with varying propagation, the environment is simply not as predictable as classical MANET deployment environments.

We presented a comparison scenario between trust establishment in Terrestrial MANET and in the underwater space, demonstrating that in order to have any reasonable expectation of performance, throughput and delay responses must be characterised before implementing trust in such environments.

We demonstrated initial, unfiltered Grey Trust assessment utilising all the available metrics (transmitted and received throughput, delay, received signal strength, transmitted power, and packet loss rate) Using the knowledge that in a 'fair' environment, trust assessments should be stable about 0.5, selected THESE to continue.

We have shown that existing frameworks are overly optimistic [Huang et al., 2010] also raised the need for a more expanded view of trust but did so with a domain-partitioning approach rather than combining trust assessments from multiple domains within networks.

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All the 'programming' for this bit is done, it's just writing. Remember to highlight the relationships between delay/distance/trust and RSSI/PLR trust. Also remember to show the RTS ratio for the mobility case, highlighting that when the environment is significantly more dynamic and delay tolerant, beta/otmf fail to take that into account.

select metrics

doesn't follow from rest of paragraph, needs to be expanded to explain the domain approach, possibly move back to 'future work' or something

7 The References Section

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Todo list

Needs to be converted to prose	2
Justify Why Grey, discuss current uses and demand. Relate back to Section 2.1	8
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select metrics	16
doesn't follow from rest of paragraph, needs to be expanded to explain the domain approach, possibly move back to 'future work' or something	16