

On the Secure Compilation of the Constant-Time Policy

Quantitative Information Flow

Luigi D. C. Soares (luigi.domenico@dcc.ufmg.br)





Outputs of a computer system



- Outputs of a computer system
- Usually unintentional

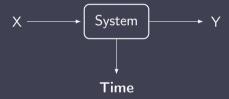


- Outputs of a computer system
- Usually unintentional



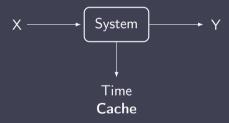


- Outputs of a computer system
- Usually unintentional



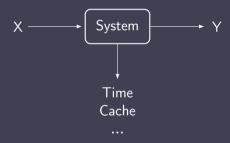


- Outputs of a computer system
- Usually unintentional



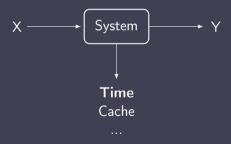


- Outputs of a computer system
- Usually unintentional





- Outputs of a computer system
- Usually unintentional







Definition 1 (Constant-Time Programming)

A program is said to implement a constant-time policy if



Definition 1 (Constant-Time Programming)

A program is said to implement a constant-time policy if its memory accesses



Definition 1 (Constant-Time Programming)

A program is said to implement a constant-time policy if its memory accesses and control flow



Definition 1 (Constant-Time Programming)

A program is said to implement a constant-time policy if its memory accesses and control flow do not depend on secret information.



Definition 1 (Constant-Time Programming)

A program is said to implement a constant-time policy if its memory accesses and control flow do not depend on secret information. In other words, the sequence of instructions and memory accesses must be the same regardless of the secret inputs.





Example 1

Consider the case of a n-bit password checker



Example 1

Consider the case of a n-bit password checker that either rejects the i-th bit or accepts the user's guess.



Example 1

Consider the case of a n-bit password checker that either rejects the i-th bit or accepts the user's guess. It could be implemented as follows:



Example 1

Consider the case of a n-bit password checker that either rejects the i-th bit or accepts the user's guess. It could be implemented as follows:



Example 1

Consider the case of a n-bit password checker that either rejects the i-th bit or accepts the user's guess. It could be implemented as follows:



Example 2

Consider, again, the case of a n-bit password checker.



Example 2

Consider, again, the case of a n-bit password checker. But, this time it either rejects or accepts the entire guessed password.



Example 2

Consider, again, the case of a n-bit password checker. But, this time it either rejects or accepts the entire guessed password. It could be implemented as follows:

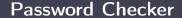


Example 2

Consider, again, the case of a n-bit password checker. But, this time it either rejects or accepts the entire guessed password. It could be implemented as follows:









► Function ctsel stands for constant-time selector





- ► Function ctsel stands for constant-time selector
- Corresponds to x86's cmov





- Function ctsel stands for constant-time selector
- Corresponds to x86's cmov
- ► LLVM's x86-cmov-converter pass replaces cmovs with branches





- ► Function ctsel stands for constant-time selector
- Corresponds to x86's cmov
- LLVM's x86-cmov-converter pass replaces cmovs with branches
- ▶ How to prove that the constant-time property is preserved?





► Barthe, Grégoire, and Laporte, "Secure Compilation of Side-Channel Countermeasures: The Case of Cryptographic "Constant-Time""



- ► Barthe, Grégoire, and Laporte, "Secure Compilation of Side-Channel Countermeasures: The Case of Cryptographic "Constant-Time"
- Observational non-interference



- ► Barthe, Grégoire, and Laporte, "Secure Compilation of Side-Channel Countermeasures: The Case of Cryptographic "Constant-Time""
- Observational non-interference
- Constant-time simulations





▶ A state is of the form $\{c, \rho\}$,



▶ A state is of the form $\{c, \rho\}$, where \overline{c} is a command and ρ is an environment



- A state is of the form $\{c, \rho\}$, where c is a command and ρ is an environment
- lacktriangle A program P is composed by a sequence of commands



- A state is of the form $\{c, \rho\}$, where c is a command and ρ is an environment
- ightharpoonup A program \overline{P} is composed by a sequence of commands
- ▶ The semantics of *P* is modelled by labelled transitions of the form

$$a \stackrel{t}{\rightarrow} {}^{n} a',$$



- A state is of the form $\{c, \rho\}$, where c is a command and ρ is an environment
- \blacktriangleright A program P is composed by a sequence of commands
- ▶ The semantics of *P* is modelled by labelled transitions of the form

$$a \stackrel{t}{\rightarrow} {}^{n} a',$$

where a and a' are states, t is the leakage and n is the number of steps



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs,



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states,



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and \mathcal{L} the set of leakage.



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and \mathcal{L} the set of leakage. Then, P is obs. non-interfering w.r.t. a binary relation ϕ on states,



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and \mathcal{L} the set of leakage. Then, P is obs. non-interfering w.r.t. a binary relation ϕ on states, written $P \models \mathrm{ONI}(\phi)$,



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and \mathcal{L} the set of leakage. Then, P is obs. non-interfering w.r.t. a binary relation ϕ on states, written $P \models \mathrm{ONI}(\phi)$, iff for all $a, a' \in P(\mathcal{I}), b, b' \in \mathcal{S}$ and $t, t' \in \mathcal{L}$,



Definition 2 (Observational Non-Interference)

Let $P(\mathcal{I})$ be the set of initial states of a program P that is given a set \mathcal{I} of inputs, let \mathcal{S} be the set of states, \mathcal{S}_f the set of final states and \mathcal{L} the set of leakage. Then, P is obs. non-interfering w.r.t. a binary relation ϕ on states, written $P \models \mathrm{ONI}(\phi)$, iff for all $a, a' \in P(\mathcal{I})$, $b, b' \in \mathcal{S}$ and $t, t' \in \mathcal{L}$,

$$a \xrightarrow{t}^{n} b \wedge a' \xrightarrow{t'}^{n} b' \wedge a \phi a' \implies t = t' \wedge (b \in \mathcal{S}_{f} \iff b' \in \mathcal{S}_{f}).$$



Definition 3 (Lockstep Simulation)

pprox is a lockstep simulation w.r.t. source and target programs S and $C=\llbracket S
rbracket$ when



Definition 3 (Lockstep Simulation)

pprox is a lockstep simulation w.r.t. source and target programs S and $C = \llbracket S \rrbracket$ when

① \forall source step $a \to b$ and target state α such that $a \approx \alpha$, \exists a target step $\alpha \to \beta$ such that $b \approx \beta$



Definition 3 (Lockstep Simulation)

pprox is a lockstep simulation w.r.t. source and target programs S and $C = \llbracket S \rrbracket$ when

- 1 \forall source step $a \to b$ and target state α such that $a \approx \alpha$, \exists a target step $\alpha \to \beta$ such that $b \approx \beta$



Definition 3 (Lockstep Simulation)

pprox is a lockstep simulation w.r.t. source and target programs S and $C = \llbracket S \rrbracket$ when

- 1 \forall source step $a \to b$ and target state α such that $a \approx \alpha$, \exists a target step $\alpha \to \beta$ such that $b \approx \beta$
- 2) \forall input parameter i, we have $S(i) \approx C(i)$

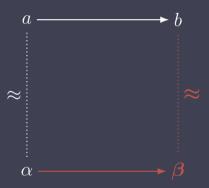


Definition 3 (Lockstep Simulation)

pprox is a lockstep simulation w.r.t. source and target programs S and $C=\llbracket S \rrbracket$ when

- ¶ \forall source step $a \to b$ and target state α such that $a \approx \alpha$, \exists a target step $\alpha \to \beta$ such that $b \approx \beta$
- 2 \forall input parameter i, we have $S(i) \approx C(i)$
- 3 \forall source and target states b and β such that $b \approx \beta$, we have that b is a final source state iff β is a final target state







Definition 4 (Lockstep CT-Simulation)

 (\equiv_S,\equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:



Definition 4 (Lockstep CT-Simulation)

 (\equiv_S, \equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:

1 \forall source steps $a \xrightarrow{t} b$ and $a' \xrightarrow{t} b'$ such that $a \equiv_S a'$, and



Definition 4 (Lockstep CT-Simulation)

 (\equiv_S, \equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:

 \forall source steps $a \xrightarrow{t} b$ and $a' \xrightarrow{t} b'$ such that $a \equiv_S a'$, and \forall target steps $\alpha \xrightarrow{\tau} \beta$ and $\alpha' \xrightarrow{\tau'} \beta'$ such that $a \approx \alpha$, $a' \approx \alpha'$, $\alpha \equiv_C \alpha'$, $b \approx \beta$ and $b' \approx \beta'$



Definition 4 (Lockstep CT-Simulation)

 (\equiv_S,\equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:

1 \forall source steps $a \xrightarrow{t} b$ and $a' \xrightarrow{t} b'$ such that $a \equiv_S a'$, and \forall target steps $\alpha \xrightarrow{\tau} \beta$ and $\alpha' \xrightarrow{\tau'} \beta'$ such that $a \approx \alpha$, $a' \approx \alpha'$, $\alpha \equiv_C \alpha'$, $b \approx \beta$ and $b' \approx \beta'$ it follows that $b \equiv_S b'$. $\beta \equiv_C \beta'$ and $\tau = \tau'$



Definition 4 (Lockstep CT-Simulation)

 (\equiv_S,\equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:

- 1 \forall source steps $a \xrightarrow{t} b$ and $a' \xrightarrow{t} b'$ such that $a \equiv_S a'$, and \forall target steps $\alpha \xrightarrow{\tau} \beta$ and $\alpha' \xrightarrow{\tau'} \beta'$ such that $a \approx \alpha$, $a' \approx \alpha'$, $\alpha \equiv_C \alpha'$, $b \approx \beta$ and $b' \approx \beta'$ it follows that $b \equiv_S b'$, $\beta \equiv_C \beta'$ and $\tau = \tau'$
- 2 \forall pairs of input parameters i and i' such that $i \varphi i'$,

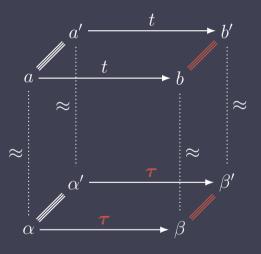


Definition 4 (Lockstep CT-Simulation)

 (\equiv_S,\equiv_C) is a lockstep CT-simulation w.r.t. \approx iff:

- 1 \forall source steps $a \xrightarrow{t} b$ and $a' \xrightarrow{t} b'$ such that $a \equiv_S a'$, and \forall target steps $\alpha \xrightarrow{\tau} \beta$ and $\alpha' \xrightarrow{\tau'} \beta'$ such that $a \approx \alpha$, $a' \approx \alpha'$, $\alpha \equiv_C \alpha'$, $b \approx \beta$ and $b' \approx \beta'$ it follows that $b \equiv_S b'$, $\beta \equiv_C \beta'$ and $\tau = \tau'$
- \forall pairs of input parameters i and i' such that $i \varphi i'$, we have that $S(i) \equiv_S S(i')$ and $C(i) \equiv_C C(i')$, where φ is a binary relation on inputs







Let $[e]_{\rho}$ be the value of expression e under environment ρ



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- \blacktriangleright Let $a.\mathrm{cmd}$ and $a.\mathrm{env}$ be the components of state a



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- Let a.cmd and a.env be the components of state a

Example 3 (Constant Folding)

Constant folding reduces expressions whose operands are known. For example:



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- \blacktriangleright Let $a.\mathrm{cmd}$ and $a.\mathrm{env}$ be the components of state a

Example 3 (Constant Folding)

Constant folding reduces expressions whose operands are known. For example:

$$(\forall \rho : [e_1]_{\rho} = 0) \implies [x := e_1 * e_2] = x := 0$$



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- Let a.cmd and a.env be the components of state a

Example 3 (Constant Folding)

Constant folding reduces expressions whose operands are known. For example:

- $(\forall \rho : [e_1]_{\rho} = 1) \implies [x \coloneqq e_1 * e_2] = x \coloneqq e_2$



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- \blacktriangleright Let $a.\mathrm{cmd}$ and $a.\mathrm{env}$ be the components of state a

Example 3 (Constant Folding)

Constant folding reduces expressions whose operands are known. For example:

- $(\forall \rho : [e_1]_{\rho} = 0) \implies \llbracket x \coloneqq e_1 * e_2 \rrbracket = x \coloneqq 0$
- $[x := e_1 * e_2] = x := e_2$

Thus, it suffices to define



- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- Let a.cmd and a.env be the components of state a

Example 3 (Constant Folding)

Constant folding reduces expressions whose operands are known. For example:

- $(\forall \rho : [e_1]_{\rho} = 0) \implies \llbracket x \coloneqq e_1 * e_2 \rrbracket = x \coloneqq 0$
- $[x := e_1 * e_2] = x := e_2$

Thus, it suffices to define

 \bullet as $[a.cmd] = \alpha.cmd \land a.env = \alpha.env$ and



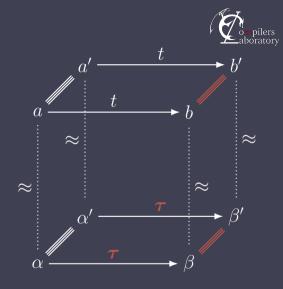
- Let $[e]_{\rho}$ be the value of expression e under environment ρ
- Let a.cmd and a.env be the components of state a

Example 3 (Constant Folding)

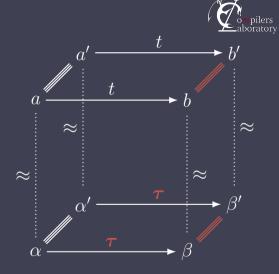
Constant folding reduces expressions whose operands are known. For example:

Thus, it suffices to define

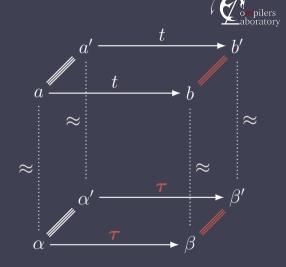
- \bullet as $[a.cmd] = \alpha.cmd \land a.env = \alpha.env$ and
- \geq_S and \equiv_C as $a.\mathrm{cmd} = b.\mathrm{cmd}$



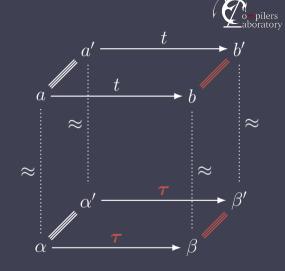
Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$



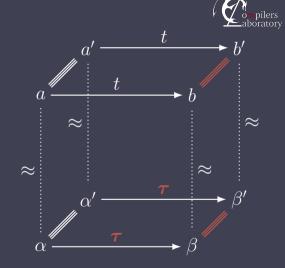
- Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$
- ▶ Let b.cmd and b'.cmd be z := x + y



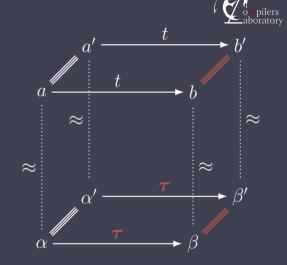
- Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$
- ▶ Let b.cmd and b'.cmd be z := x + y
- \blacktriangleright Suppose k always evaluates to 0



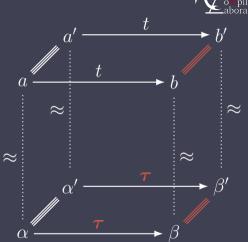
- Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$
- ▶ Let b.cmd and b'.cmd be z := x + y
- Suppose k always evaluates to 0
- ▶ Then α .cmd α' .cmd are y := 0



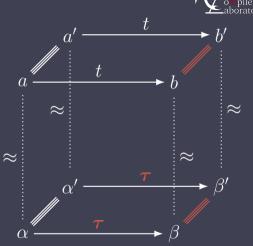
- Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$
- ▶ Let b.cmd and b'.cmd be z := x + y
- \blacktriangleright Suppose k always evaluates to 0
- ► Then α .cmd α' .cmd are y := 0
- ▶ Similarly, β .cmd and β' .cmd are z := x



- Let a.cmd and a'.cmd be y := A[i] * k
- Let b.cmd and b'.cmd be z := x + y
- Suppose k always evaluates to 0
- Then α .cmd α' .cmd are y := 0
- Similarly, β .cmd and β' .cmd are z := x
- $t = t' \cdot (A, [i]_{\rho_{\alpha}})$ and $[i]_{\rho_{\alpha}} = [i]_{\rho_{\alpha}}$

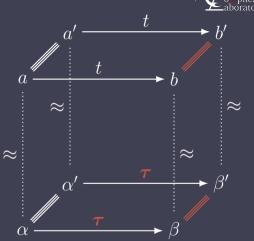


- Let $a.\operatorname{cmd}$ and $a'.\operatorname{cmd}$ be y := A[i] * k
- Let b.cmd and b'.cmd be z := x + y
- Suppose k always evaluates to 0
- Then α .cmd α' .cmd are y := 0
- Similarly, β .cmd and β' .cmd are z := x
- $\vdash t = t' \cdot (A, [i]_{\rho_a})$ and $[i]_{\rho_a} = [i]_{\rho_a}$
- What is the leakage τ and is it the same in both steps?



ompiler: aborato

- Let $a.\mathrm{cmd}$ and $a'.\mathrm{cmd}$ be $y \coloneqq A[i] * k$
- ▶ Let b.cmd and b'.cmd be z := x + y
- Suppose k always evaluates to 0
- ► Then α .cmd α' .cmd are y := 0
- ► Similarly, β .cmd and β' .cmd are z := x
- $ightharpoonup t = t' \cdot (A, [i]_{\rho_a})$ and $[i]_{\rho_a} = [i]_{\rho_{a'}}$
- What is the leakage τ and is it the same in both steps?
- $\tau = \tau'$







Relation to QIF



Labelled transitions

► Information-theoretic channels

Relation to QIF



- Labelled transitions
- Leakage as a trace of events

- Information-theoretic channels
- Leakage as a real number

Relation to QIF



- Labelled transitions
- Leakage as a trace of events
- Constant-time simulation

- ► Information-theoretic channels
- Leakage as a real number
- Refinement

References



- Alvim, Mário S et al. (2020). *The Science of Quantitative Information Flow.* Springer.
- Barthe, Gilles, Benjamin Grégoire, and Vincent Laporte (2018). "Secure Compilation of Side-Channel Countermeasures: The Case of Cryptographic "Constant-Time". In: 2018 IEEE 31st Computer Security Foundations Symposium (CSF), pp. 328–343. DOI: 10.1109/CSF.2018.00031.