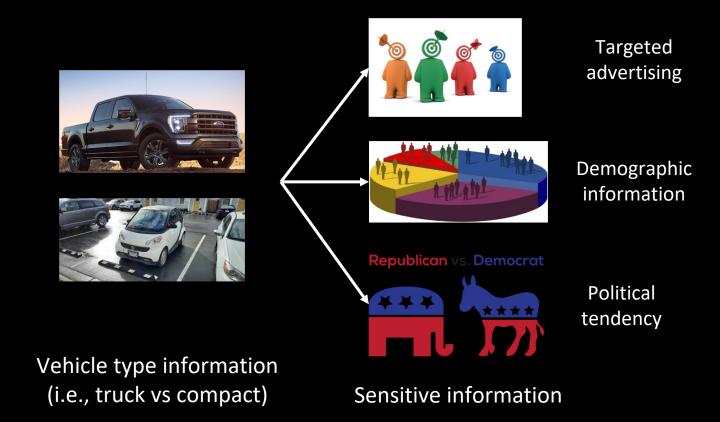
Guess Which Car Type I am Driving? Information Leak via Driving Apps

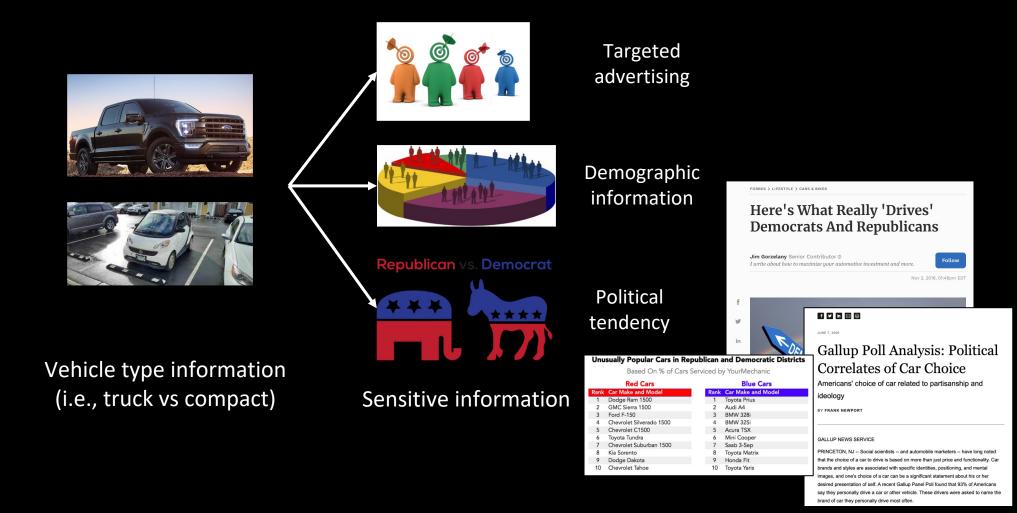
Dongyao Chen, Mert D. Pesé, and Kang G. Shin



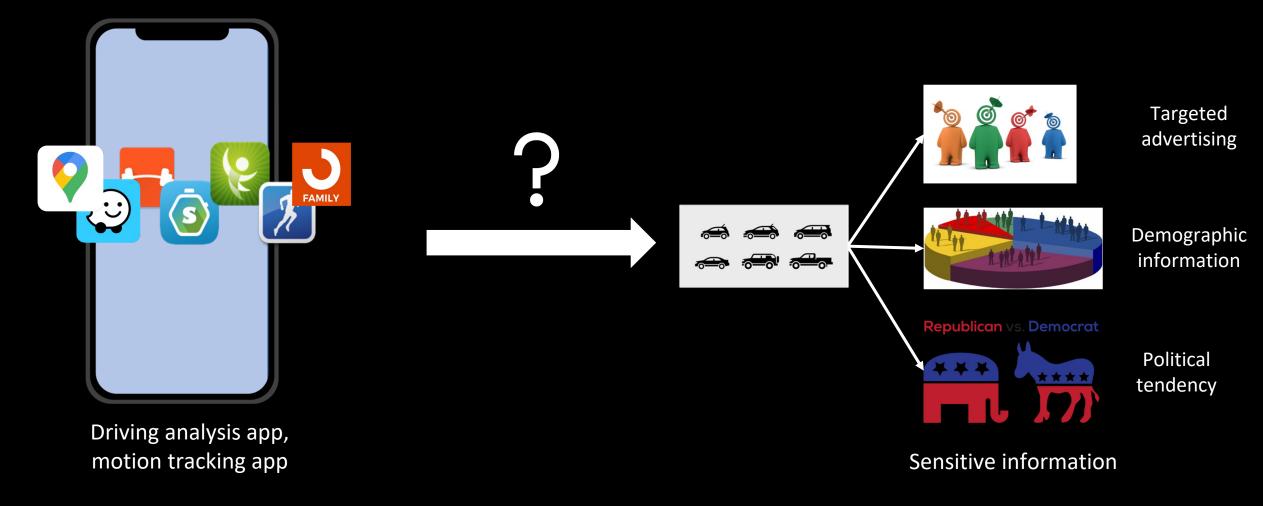
Vehicle Type can link to Sensitive Info



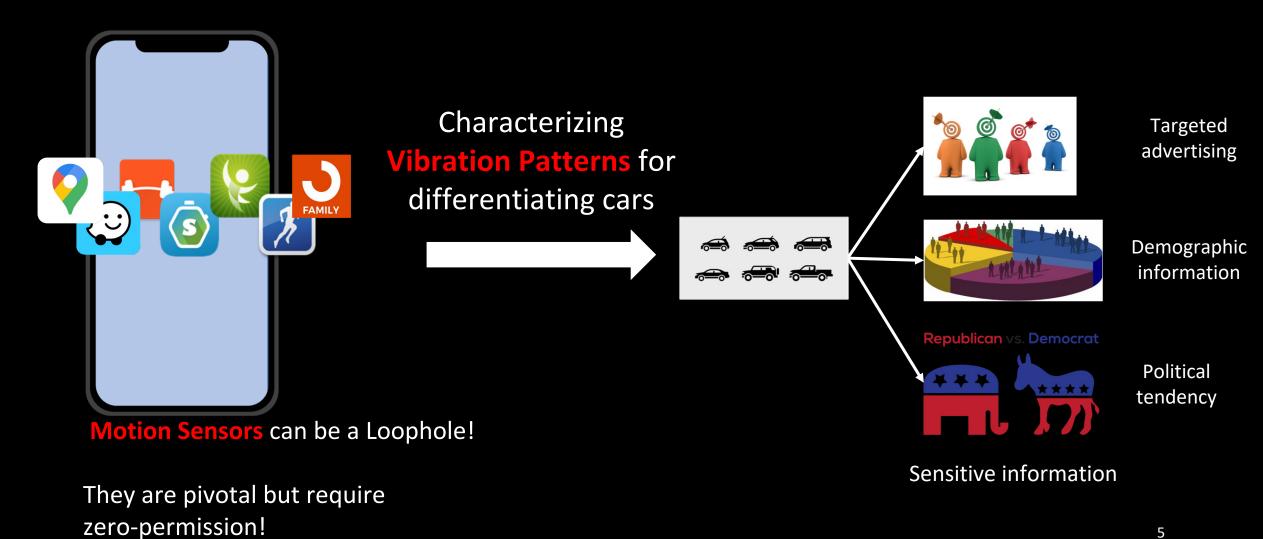
Vehicle Type can link to Sensitive Info



Can our Smartphone Stealthily Leak this Info?

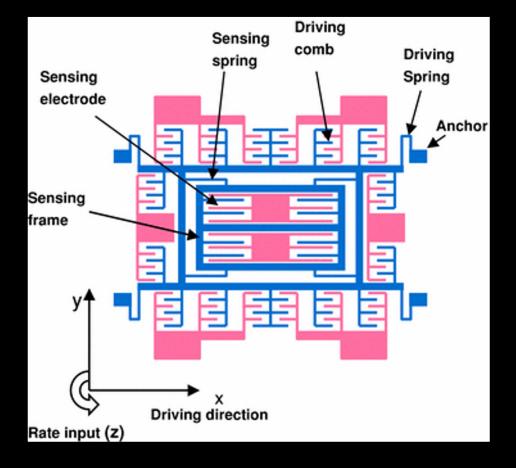


Can our Smartphone Stealthily Leak this Info?



Sensing Vibrations with Motion Sensors (IMU)

• The embedded oscillator of accelerometer and gyroscopes can be used for sampling high-speed vibrations



[Michalevsky et. al 2014]

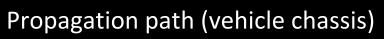
Threat Model

Moving vehicle



Source (engine, wheels)





Idling vehicle





IMU Targeted data messages (ads, notifications)

> Receiver (malicious app eavesdrops IMU data)

6

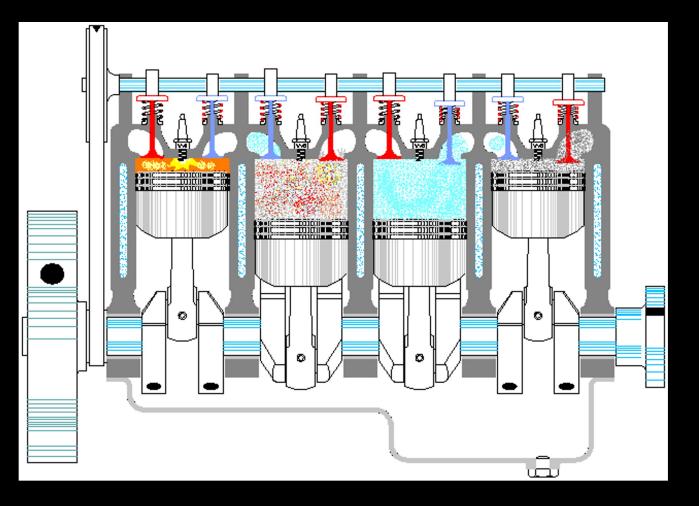
Inferring Type of an Idling and Moving Vehicle

Vibration pattern varies depends on whether the vehicle is moving

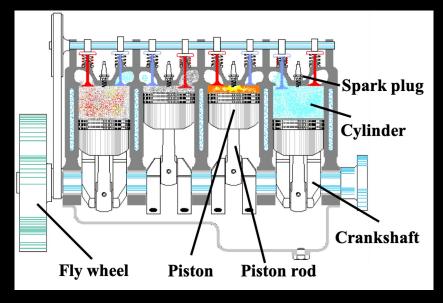


Idling vehicle

Moving vehicle



- Engine is the dominant source of vibration when car is idling
- Engine is representative of car types
 - Hybrid: 3~4-cylinder
 - Pickup truck: 6~8-cylinder



I. Combustion $f_C = \frac{RPM}{60}\frac{C}{2}$

2. N-th order overtones:

order $f_{C,N} = N f_C$

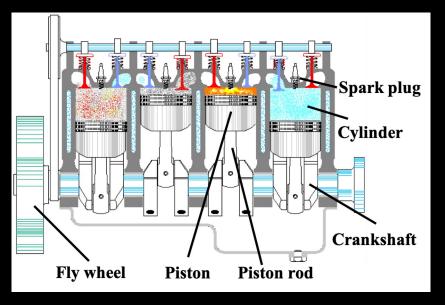
3. Aliased frequency that can be detected by motion sensors

 $f^a_{C,N} = \left| f_{C,N} - K f_s \right|$

4. The detectable engine overtone at specific engine RPM is:

$$f_{C,N}^{a}(RPM) = \left| N \frac{RPM}{60} \frac{C}{2} - Kf_{s} \right|$$
$$0 \le f_{C,N}^{a} \le \frac{f_{s}}{2} \quad K \in \mathbb{Z}$$

The first 2 order overtones are the strongest



Overtone order N=1 N=2N=3# cylinder [20 33.3] [33.3, 50] [0, 40]4 [30, 50]6 [0, 40][0, 50]8 [33.3, 50] [0, 33.3][0, 50]

The detectable engine overtone at specific engine RPM:

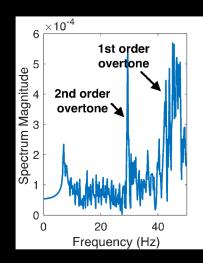
$$f_{C,N}^{a}(RPM) = \left| N \frac{RPM}{60} \frac{C}{2} - Kf_{s} \right|$$
$$0 \le f_{C,N}^{a} \le \frac{f_{s}}{2} \quad K \in \mathbb{Z}$$

ephilos vertone 2 20 40 Frequency (Hz)

4-cylinder

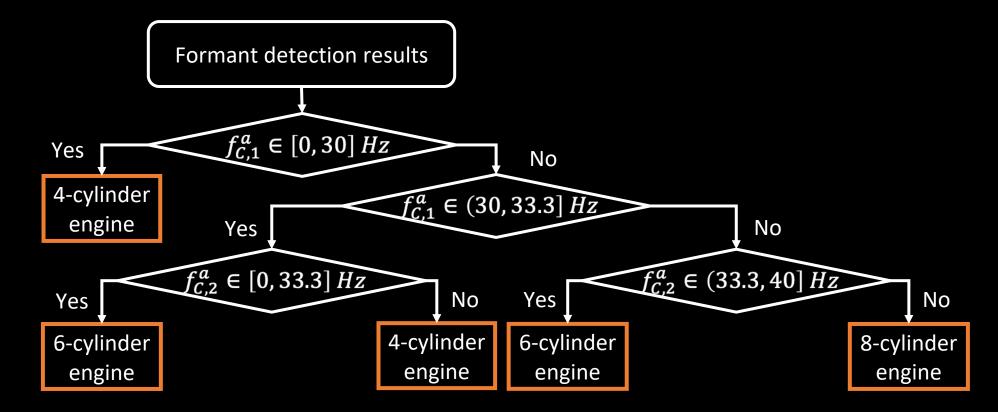
2 ×10⁻³ 1st order overtone 1.5 2nd order overtone 0.5 0 0 20 40 Frequency (Hz)

6-cylinder

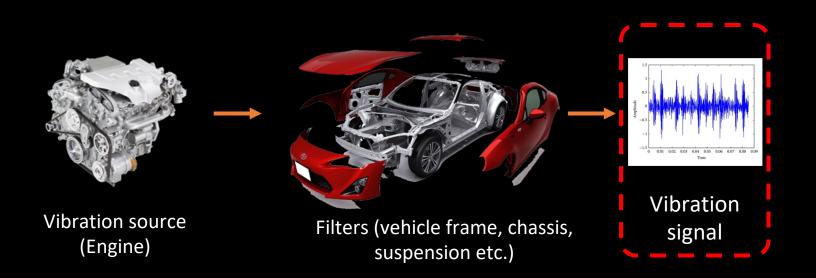


8-cylinder

A decision tree can be constructed based on the distribution of $f_{C,N}^a$

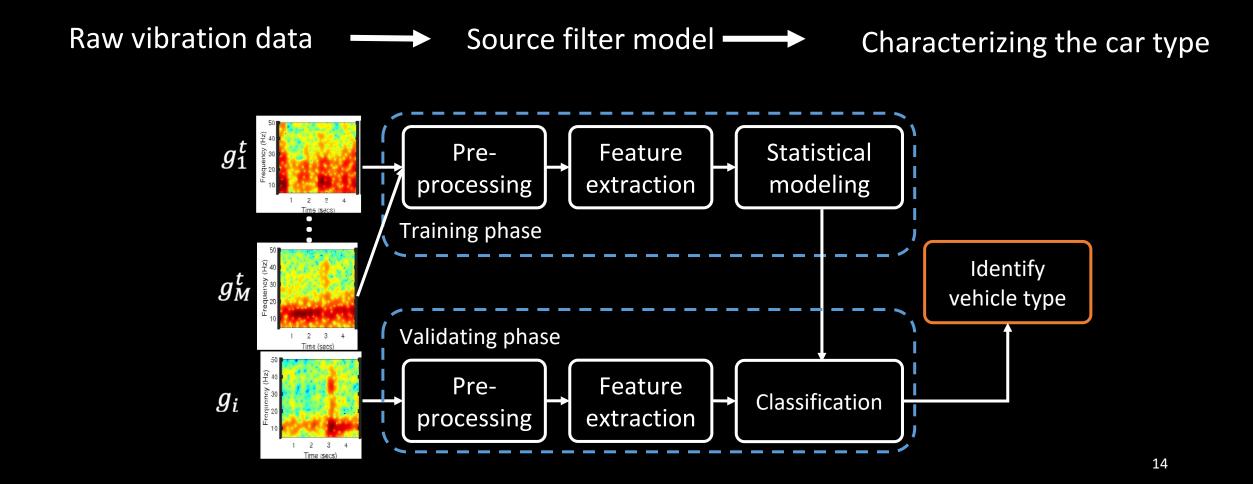


Inferring Type of a Moving Vehicle

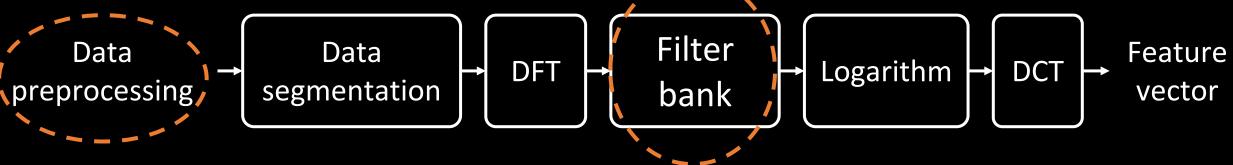


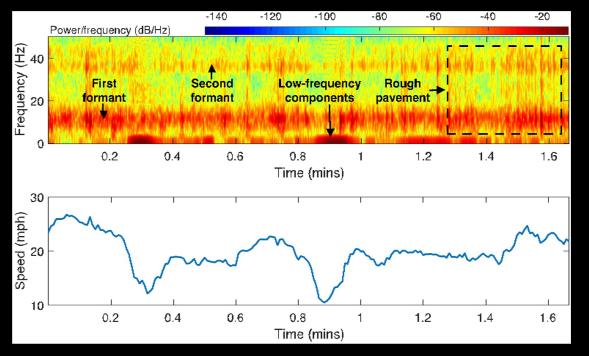
Inferring Type of a Moving Vehicle

Insights from the pipeline of speaker recognition



Feature Extraction: Adapt to Vehicle Vibration





Spectral features when the vehicle is moving

- Maneuver generates the lowfrequency components (<5 Hz)
- 2. Key formants are distinguishable even on rough pavement

Evaluation Setting

Cases	Vehicle type	Experimental vehicle(s)
C-1	Compact	Toyota Corolla 2009; Hyundai Elantra 2008; Nissan Sentra 2018
C-2	Mid-size	Honda Accord 2006, 2013; Toyota Camry 2010, Toyota Camry 2010, 2011; Ford Fusion 2018; Mercedes Benz C180 2016
C-3	SUV	Honda CRV 2013, 2014; Jeep Campus 2014; Ford Explorer 2011, 2016
C-4	Pickup truck	GMC Sierra 2015, 2016; Ford F-150 2017

• For each vehicle type we extract the gyroscope sensor data from idling and moving stages

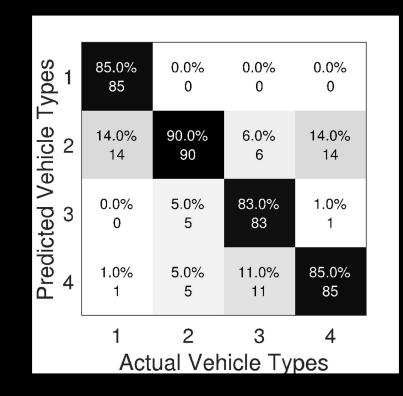
Evaluation

Identifying types of idling vehicles

# cylinder	Precision	Recall	F-1
4	0.82	0.82	0.82
6	0.67	0.50	0.57
8	0.67	1.00	0.80

Evaluation

Identifying types of moving vehicles



The overall accuracy is 85.75%

Conclusion

- VeFi exploits the vibration pattern to differentiate vehicle types
- A high-frequency vibration pattern can characterize:
 - Engine type for idling cars
 - Car body type for moving cars

Thanks! Q&A

Research Presented by:





