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Sébastien Tixeuil (Eds.)

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Preface

This volume contains the 27 regular papers and the abstracts of three invited keynotes that were presented at the Ninth International Symposium on Stabilization, Safety, and Security of Distributed Systems (SSS) held November 14–16, 2007 in Paris, France.

SSS, the International Symposium on Stabilization, Safety, and Security of Distributed Systems, is a prestigious international forum for researchers and practitioners in design and development of fault-tolerant distributed systems with self-* properties, such as self-stabilizing, self-configuring, self-organizing, self-managing, self-repairing, self-healing, self-optimizing, self-adaptive, and self-protecting properties. It started as the Workshop on Self-Stabilizing Systems (WSS), which was first held at Austin in 1989. From the second WSS in Las Vegas in 1995, the forum was held biennially, at Santa Barbara (1997), Austin (1999), Lisbon (2001), San Francisco (2003), and Barcelona (2005). With the growth of the research field of self-stabilization, the title of the forum changed to the Symposium on Self-Stabilizing Systems (SSS) in 2003. Since 2005, SSS was run annually to encourage the rapid and sustained growth of the field, and the 2006 edition was held in Dallas. In 2006, following the demand for self-stabilization in various areas of distributed computing including peer-to-peer networks, wireless sensor networks, mobile ad hoc networks, and robotic networks, the scope of the symposium was extended to cover all safety and security-related aspects of self-* systems. The title of the symposium changed to the International Symposium on Stabilization, Safety, and Security of Distributed Systems (SSS).

This year, we received 64 submissions from 22 countries. Each submission was carefully reviewed by four to six Program Committee members with the help of external reviewers, and the Program Committee selected the 27 papers. It is worthwhile noticing that the overall quality of submissions was excellent and there are many papers that we had to reject because of organization constraints yet deserved to be published. The three invited keynotes dealt with hot topics absorbing the interest of attendees: “The Power of Cryptographic Attacks: Is Your Network Really Secure Against Side Channels Attacks and Malicious Faults?” by Jean-Jacques Quisquater, “Role-Based Self-Configuration of Sensor Networks” by Kay Römer, and “Robots and Molecules” by Masafumi Yamashita. Following the recent tradition of SSS, Anurag Dasgupta, Sukumar Ghosh, and Xin Xiao received the Best Paper Award for their paper, “Probabilistic Fault-Containment.”

On behalf of the Program Committee, we would like to thank all authors of submitted papers for their support. We also thank the members of the Steering Committee for their invaluable advice. We wish to express our appreciation to the Program Committee members and additional external reviewers for their tremendous effort and excellent reviews. We gratefully acknowledge the Organizing Committee members for their generous contribution to the success

of the symposium. Paper submission, selection, and generation in the proceedings was greatly eased by the use of the EasyChair conference system (<http://www.easychair.org>). We wish to thank the EasyChair creators and maintainers for their commitment to the scientific community.

“We gratefully acknowledge the financial support from *Microsoft Corporation*, the *Laboratoire de Recherche en Informatique (LRI)*, the *Laboratoire d’Informatique de Paris 6 (LIP6)*, and the *Présidence de l’Université Paris Sud XI*”.

November 2007

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The Power of Cryptographic Attacks: Is Your Network Really Secure Against Side Channels Attacks and Malicious Faults?

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Abstract. When speaking about attacks against networks and computers, people mainly think today about viruses, worms, Trojans, keyloggers, denial of services, etc.

In the last ten years a lot of new attacks were found against servers and smart cards. First are side-channels attacks: those are by using "esoteric" channels to obtain protected, secure and private informations. Esoteric here means very often channels related to the communication channel (time of interaction), processors (power, electromagnetic radiations, caches, branching, etc.). Second are the malicious faults related to secret key cryptography. The interaction of cryptographic algorithms with malicious faults must be carefully known and understood: one error sometimes means a totally broken system.

We will survey the field with a focus on distributed systems and networks.

Role-Based Self-configuration of Sensor Networks

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Abstract. Wireless sensor networks consist of so-called sensor nodes – small untethered computing devices equipped with sensors, a wireless radio, a processor, and autonomous power supply. Large and dense networks of these devices can be deployed unobtrusively in the physical environment in order to monitor a wide variety of real-world phenomena with unprecedented quality and scale while only marginally disturbing the observed physical processes.

Many sensor network applications require some form of self-configuration, where sensor nodes take on specific functions in the network. Configuration of a sensor network is particularly challenging, as the anticipated large number of sensor nodes participating in a network typically precludes manual configuration of individual nodes. Additionally, pre-deployment configuration is often infeasible because some configuration parameters such as node location and network neighborhood are typically unknown prior to deployment. Also, node parameters may change over time, necessitating dynamic re-configuration.

In this talk we present a framework for the development of self-configuring sensor networks known as *generic role assignment*. The key idea is to consider self-configuration as the problem of assigning a *role* to each sensor node such that certain global constraints are satisfied. Both the set of available roles and the constraints can be specified by the developer using a declarative specification language. These specifications are compiled and executed in the sensor network, where a distributed role assignment algorithm finds an assignment of roles to sensor nodes that is compliant with the specification. Assigned roles are updated to reflect changes in the sensor network resulting, for example, from addition or removal of nodes. The role assignment algorithms are efficient regarding the communication overhead and robust with respect to message loss.

Using this framework, a variety of different self-configuration problems can be implemented. Example problems include *coverage* (assign roles **ACTIVE** and **SLEEP**, such that few active nodes cover the area of interest with their sensors while the remaining nodes can be turned into a power-saving sleep mode) or *clustering* (assign roles **SLAVE**, **GATEWAY**, and **HEAD** such that each slave has a cluster head neighbor where cluster heads are interconnected by gateway nodes to form a connected backbone). These and other problems can be specified with few lines of code using the declarative specification language, which effectively shields the developer from low-level implementation details.

Robots and Molecules

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Abstract. We survey some of the recent theoretical works about autonomous mobile robot systems and then discuss the possibility of extending robot models to analyze molecular computing systems. There are two types of robot systems appearing in the Distributed Computing literature. One is a self-reconfigurable system, which consists of a number of identical robotic modules that can connect to, disconnect from, and relocate relatively to adjacent modules. A behaviour of a self-reconfigurable system looks like the life game and we are interested in designing an algorithm (local map) that makes the whole system behave in a consistent way. The other model is an autonomous mobile robot system, which consists of mobile robots with eye sensors as communication devices. The formation problem of a given geometrical pattern has been discussed extensively. Although those two systems have some common features and common goals, they were proposed independently and have been investigated separately.

After surveying some of works on those robot systems, we introduce some works in molecular computing. We explain some of the examples in which those robot systems appear naturally. We then argue some problems that arise from the molecular computing applications. A key coincidence between the robot models and the molecular computing is that they are systems composed of anonymous modules.