

# Robust Physical-World Attacks on Deep Learning Models

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Chaowei Xiao, Atul Prakash, Tadayoshi Kohno, and Dawn Song

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# Introduction

- DNNs are vulnerable to human-imperceptible adversarial perturbations.

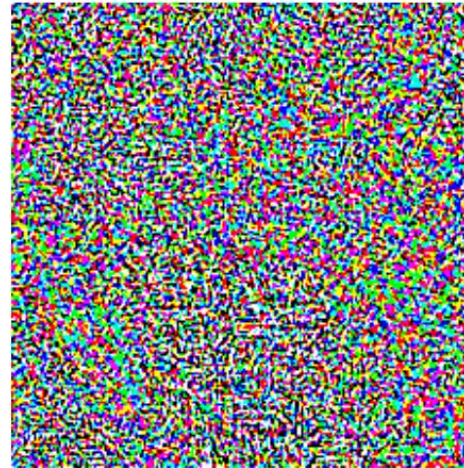


$x$

“panda”

57.7% confidence

+ .007 ×



$\text{sign}(\nabla_x J(\theta, x, y))$

“nematode”

8.2% confidence

=



$x +$

$\epsilon \text{sign}(\nabla_x J(\theta, x, y))$

“gibbon”

99.3 % confidence

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- *Experimental setting:* Construct **printable stickers** that can be cut out and placed on **physical road signs** to cause a DNN classifier to misclassify the road sign.
- *Adversarial setting:* The proposed method is a **targeted white-box attack**.



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2. Account for spatial constraints of the adversarial perturbation
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4. Account for fabrication errors (e.g., error introduced when printing the perturbation)

## General Attack Method

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- Lagrangian-relaxed form:

$$\operatorname{argmin}_{\delta} \underbrace{\lambda \|\delta\|_p}_{\text{L-}p \text{ norm of } \delta} + \underbrace{J(f_\theta(x + \delta), y^*)}_{\text{Loss function}}$$

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- Collect set of images  $X^V$  of object class  $o$  (e.g., stop sign) consisting of:
  - *Physical transformations*: real-world images in varying physical conditions, such as lighting, distance, angle and weather
  - *Synthetic transformations*: random crops, varying brightness levels

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$$\operatorname{argmin}_{\delta} \lambda \|\delta\|_p + J(f_{\theta}(x + \delta), y^*)$$



Alignment transformation

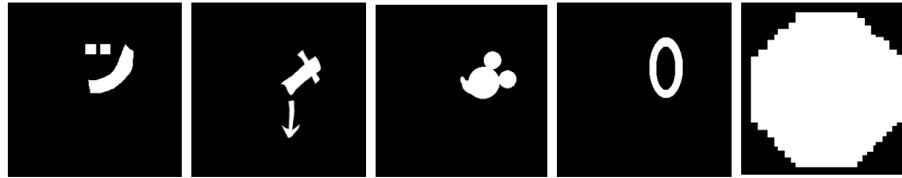
$$\operatorname{argmin}_{\delta} \lambda \|\delta\|_p + \mathbb{E}_{x_i \sim X^V} J(f_{\theta}(x_i + T_i(\delta)), y^*)$$

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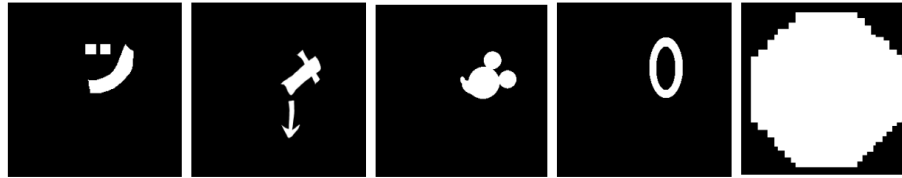
- Utilize a mask  $M_x \in \mathbb{R}^d$  to constrain the region of the image where the perturbation can exist.



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$$\operatorname{argmin}_{\delta} \lambda \|\delta\|_p + \mathbb{E}_{x_i \sim X^v} J(f_{\theta}(x_i + T_i(\delta)), y^*)$$



$$\operatorname{argmin}_{\delta} \lambda \|M_x \cdot \delta\|_p + \mathbb{E}_{x_i \sim X^v} J(f_{\theta}(x_i + T_i(M_x \cdot \delta)), y^*)$$

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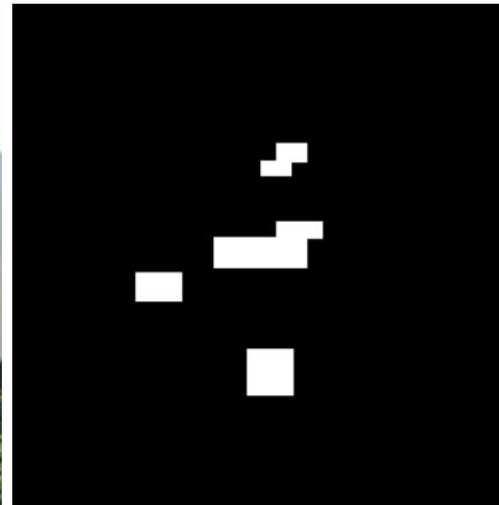
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2. Threshold the highly-activated perturbation regions.



Final Mask

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- Attack two trained classifiers:
  - LISA-CNN: Trained on LISA road sign classification dataset. 91% accuracy on test set.
  - GTSRB-CNN: Trained on GT-SRB road sign classification dataset. 95.7% accuracy on test set.

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- Two types of experiments:
  - Stationary (lab) tests
  - Drive-by (field) tests

# Results: Lab Test

Table 1: Sample of physical adversarial examples against LISA-CNN and GTSRB-CNN.




























Distance/Angle	Subtle Poster	Subtle Poster Right Turn	Camouflage Graffiti	Camouflage Art (LISA-CNN)	Camouflage Art (GTSRB-CNN)
5' 0°					
5' 15°					
10' 0°					
10' 30°					
40' 0°					
Targeted-Attack Success	100%	73.33%	66.67%	100%	80%

Table 5: A camouflage art attack on GTSRB-CNN. See example images in Table 1. The targeted-attack success rate is 80% (true class label: Stop, target: Speed Limit 80).

Distance & Angle	Top Class (Confid.)	Second Class (Confid.)
5' 0°	Speed Limit 80 (0.88)	Speed Limit 70 (0.07)
5' 15°	Speed Limit 80 (0.94)	Stop (0.03)
5' 30°	Speed Limit 80 (0.86)	Keep Right (0.03)
5' 45°	Keep Right (0.82)	Speed Limit 80 (0.12)
5' 60°	Speed Limit 80 (0.55)	Stop (0.31)
10' 0°	Speed Limit 80 (0.98)	Speed Limit 100 (0.006)
10' 15°	Stop (0.75)	Speed Limit 80 (0.20)
10' 30°	Speed Limit 80 (0.77)	Speed Limit 100 (0.11)
15' 0°	Speed Limit 80 (0.98)	Speed Limit 100 (0.01)
15' 15°	Stop (0.90)	Speed Limit 80 (0.06)
20' 0°	Speed Limit 80 (0.95)	Speed Limit 100 (0.03)
20' 15°	Speed Limit 80 (0.97)	Speed Limit 100 (0.01)
25' 0°	Speed Limit 80 (0.99)	Speed Limit 70 (0.0008)
30' 0°	Speed Limit 80 (0.99)	Speed Limit 100 (0.002)
40' 0°	Speed Limit 80 (0.99)	Speed Limit 100 (0.002)

# Results: Field Test

Perturbation	Attack Success	A Subset of Sampled Frames $k = 10$
Subtle poster	100%	
Camouflage abstract art	84.8%	



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## Conclusions

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- No! This work did not conduct any experiments with an autonomous vehicle. To make this conclusion, a more complete attack must be proposed that targets the full autonomous driving pipeline.

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**Any questions? Please send me an email! [l6rowe@uwaterloo.ca](mailto:l6rowe@uwaterloo.ca)**