

Active Search on Post-Compromise Graphs

When does topology-aware planning actually help the analyst?

K. Stefanopoulos

Supervisors: A. Minculescu, F. Oliehoek
Sequential Decision Making Group

MOTIVATION

The Problem

A breach hits. A few machines are infected, most are clean. An analyst can inspect only a handful, one at a time.

Which machines do you check first?

Active search: find the most compromised hosts before the budget runs out, without assuming the layout is known.

THE SIGNAL

Core Idea: the parameter ρ

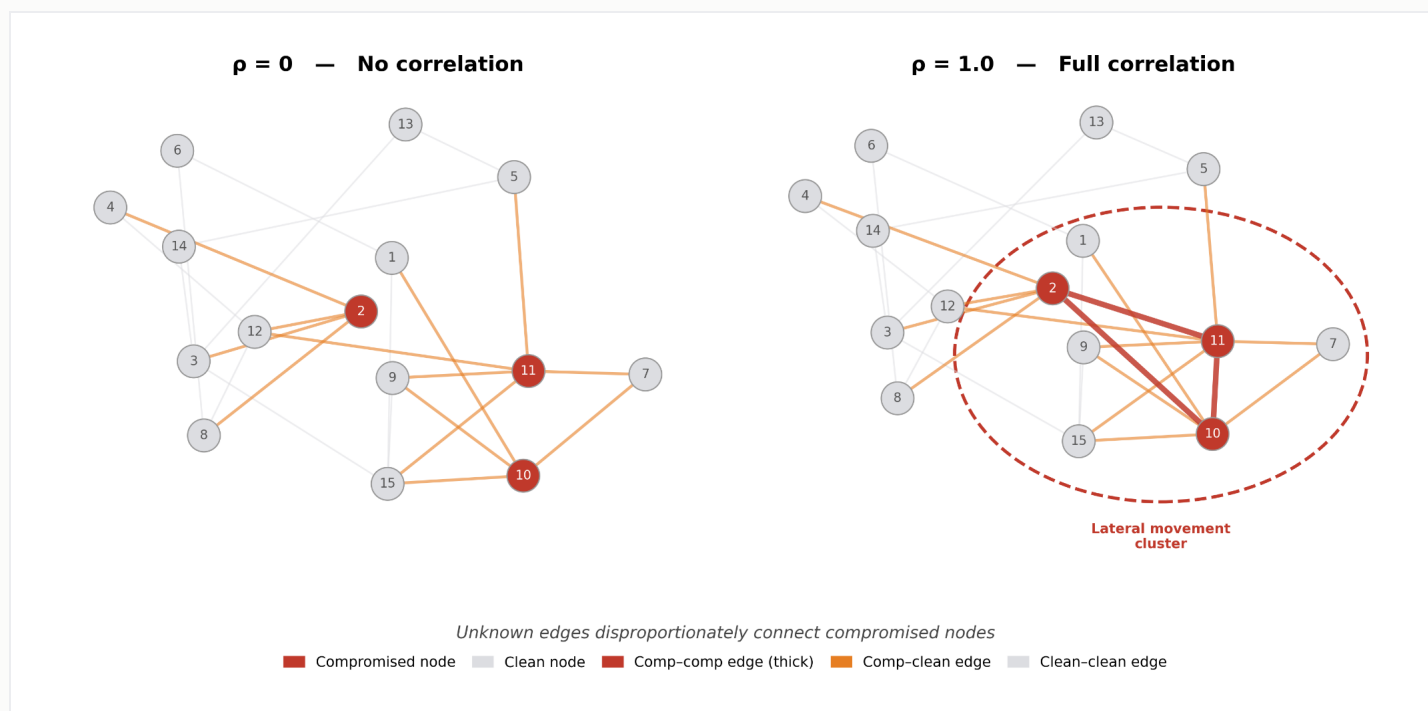
Infected machines connect to one another more than to clean ones. The parameter ρ sets how strong that pattern is.

$\rho = 0$

no hidden links

$\rho = 1$

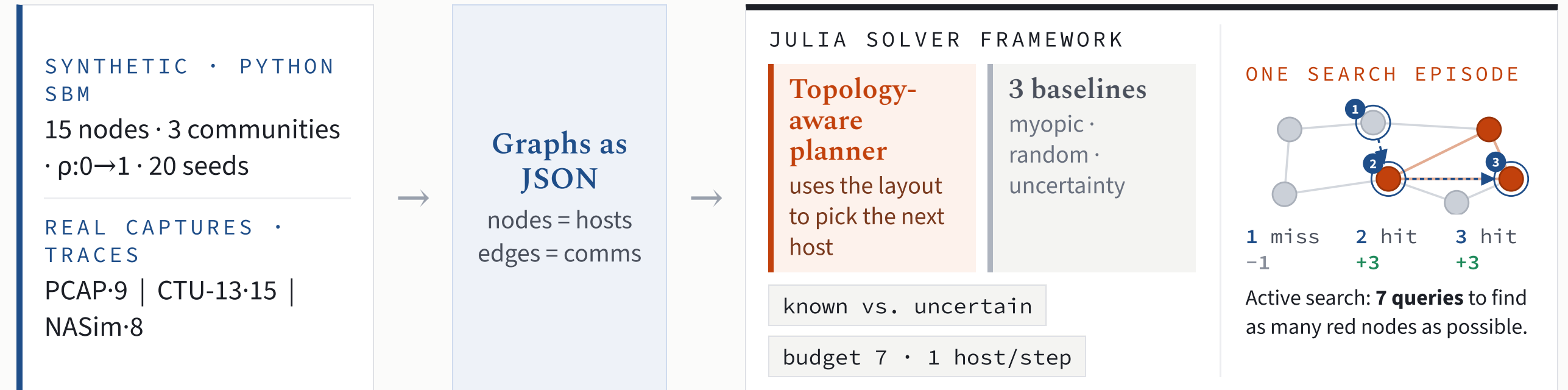
every infected pair linked



As ρ rises, unknown edges concentrate among compromised nodes, forming a lateral-movement cluster.

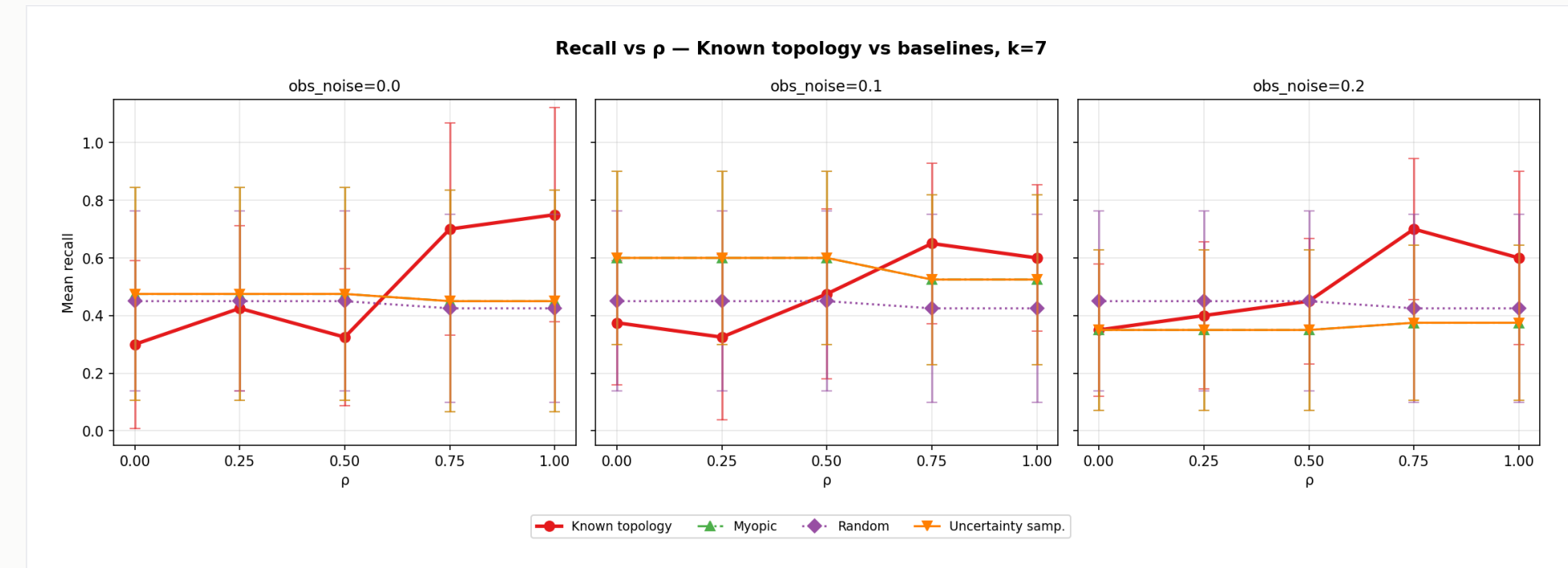
Methodology

EXPERIMENTAL SETUP $\approx 2,300$ jobs · DelftBlue HPC · ≈ 46 core-hours



Each episode records recall · cumulative reward · belief-filter diagnostics.

Main Result FINDINGS



Known topology (red) is the only solver whose recall climbs with ρ ; the three baselines stay flat at 0.43–0.48.

2.5x

more infected hosts found as the signal strengthens, when topology is known ($p = 0.0023$).

When the pattern is weak, the planner does *worse than random*, chasing structure that carries no signal.

BOTTOM LINE

Topology-aware planning wins *only* when all three conditions hold. Miss any one, and random guessing does as well or better.

1 Layout is known

Without it the planner's belief collapses within a few steps.

2 Pattern is strong

If infected hosts are no more connected, there is nothing to find.

3 Network is dense

On sparse graphs even a strong pattern gets lost.