

Practical and Accurate Local Edge Differentially Private Graph Algorithms

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Research Track 28 : Social Networks



Local Edge Differentially Private

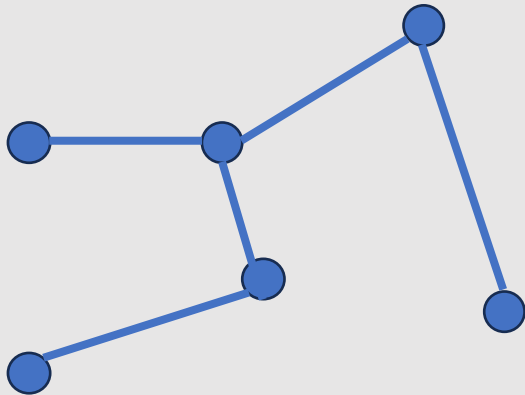
Differential Privacy (DP) [Dwork-McSherry-Nissim-Smith '06]

An algorithm A is ϵ -differentially private if for all pairs of neighboring inputs G and G' and all sets of possible outputs S , the following holds:

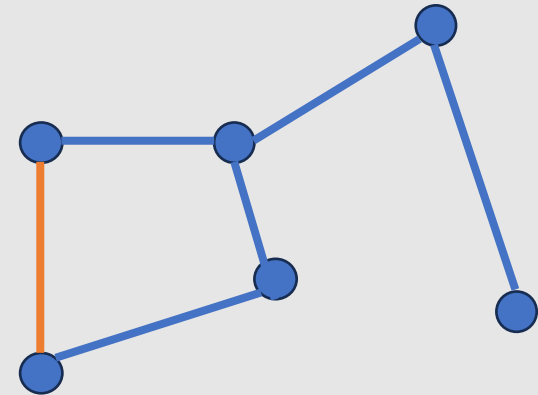
$$Pr[A(G) \in S] \leq e^\epsilon \cdot Pr[A(G') \in S]$$

Local **Edge** Differentially Private

Edge-neighboring graphs : differ in **one edge**



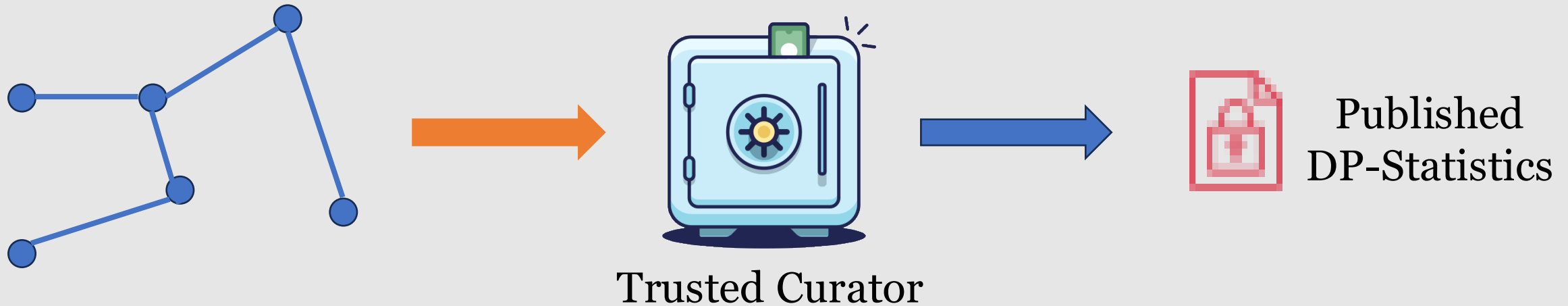
G



G'

Local Edge Differentially Private

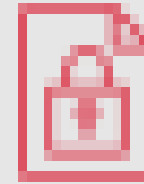
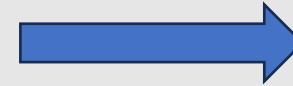
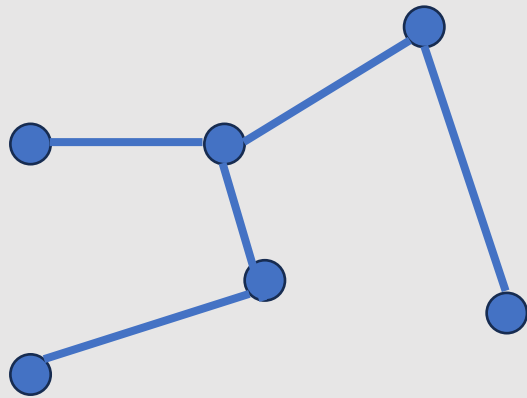
Central Model of DP



- Trust in a central authority, that collects the raw data
- Runs a DP-mechanism and publishes the privatized statistics

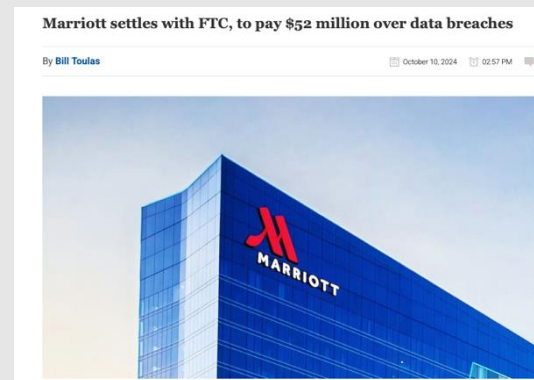
Local Edge Differentially Private

Central Model of DP



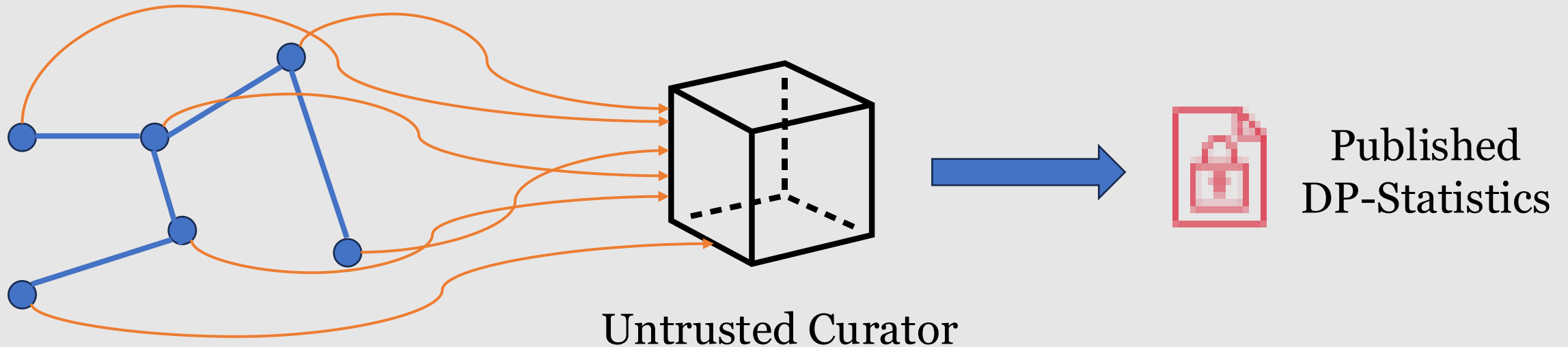
Published
DP-Statistics

Trusted Curator



Local Edge Differentially Private

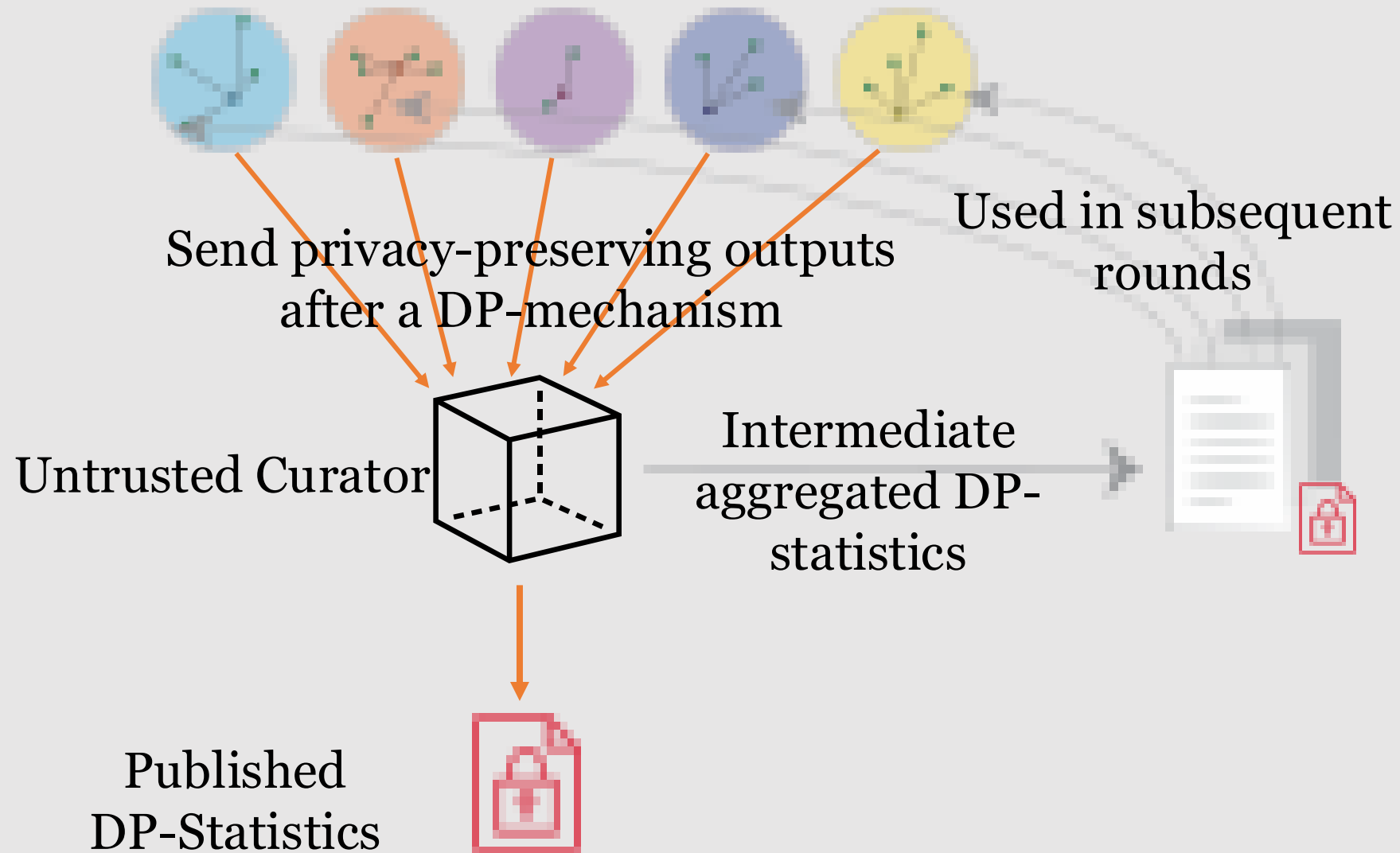
Local Model of DP



- Stronger notion of privacy: Individual trusts no one!
- Each node runs a DP-mechanism independently and sends its privatized output to the curator
- The curator aggregates these outputs to publish the statistics.

LEDP Model

Each user (node) stores **only** their adjacency list



- Round based synchronous algorithm
- Only privacy-preserving outputs are shared
- No raw data is ever shared
- No trust in any individual
- Distributed in nature

Challenges

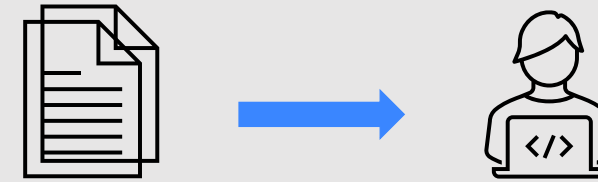
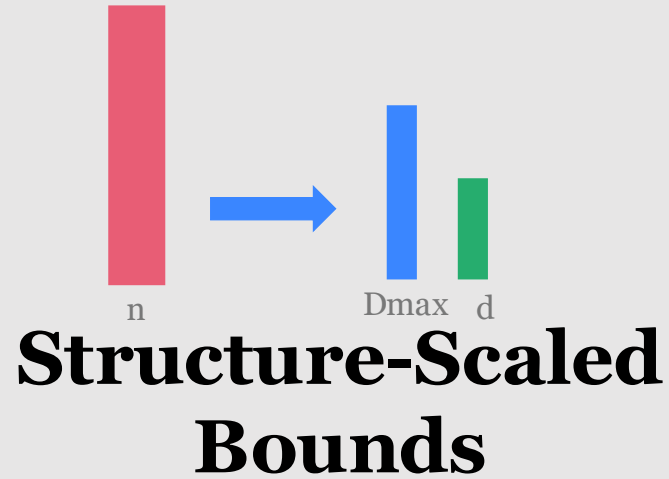
Theory-Practice Gap

**Naïve Randomized
Response Methods**

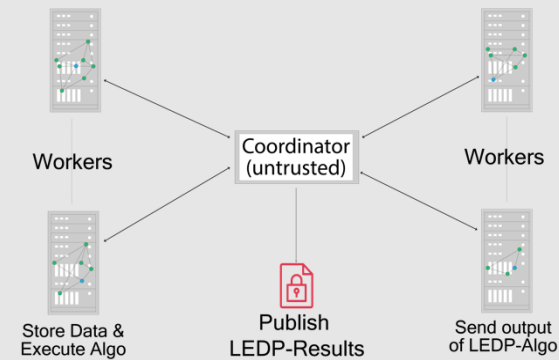
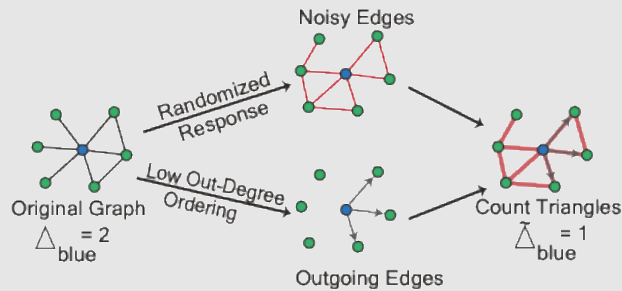
**Graph Size Scaled
Bounds**

**No Practical
Framework**

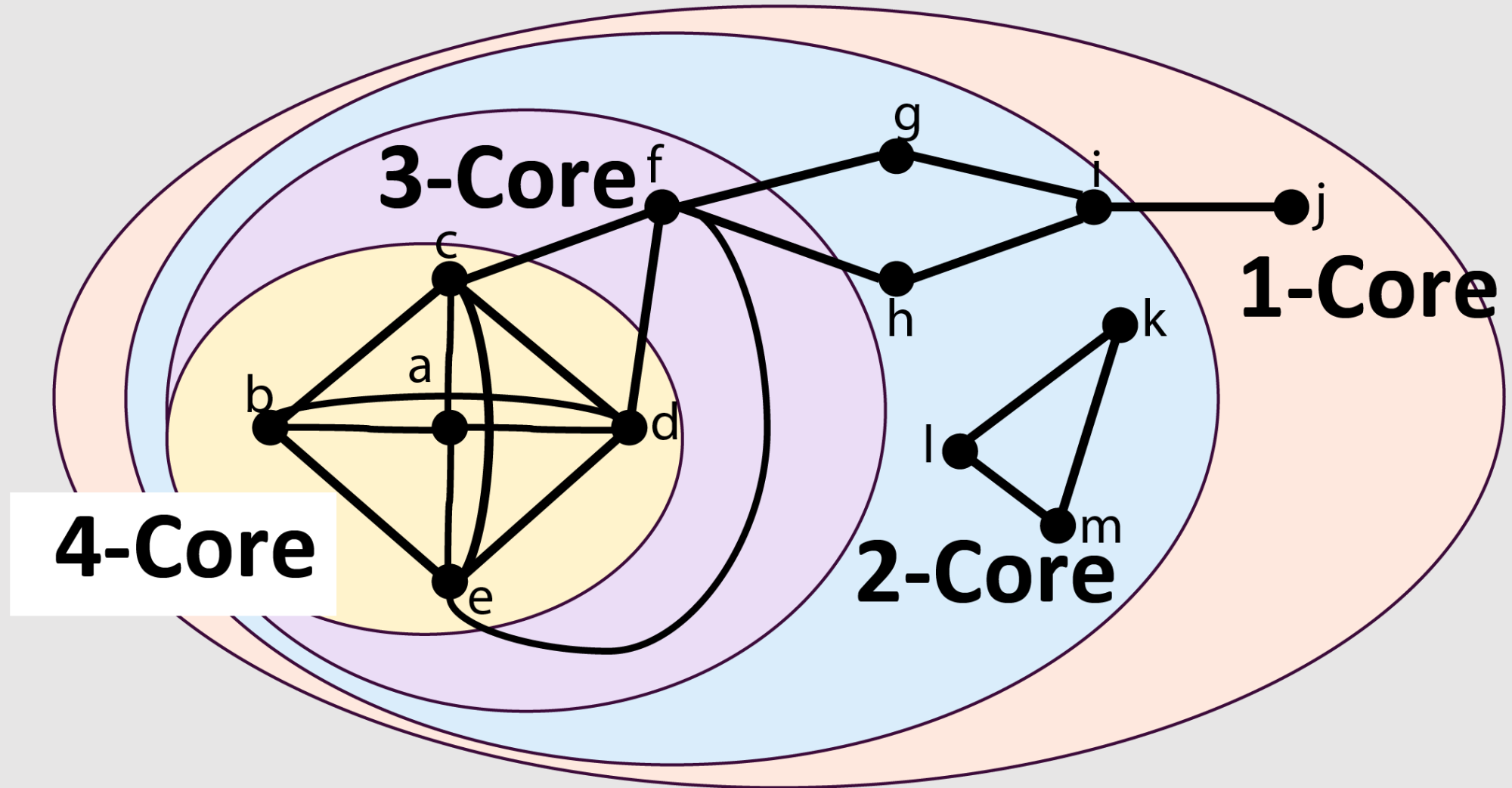
Our Contributions



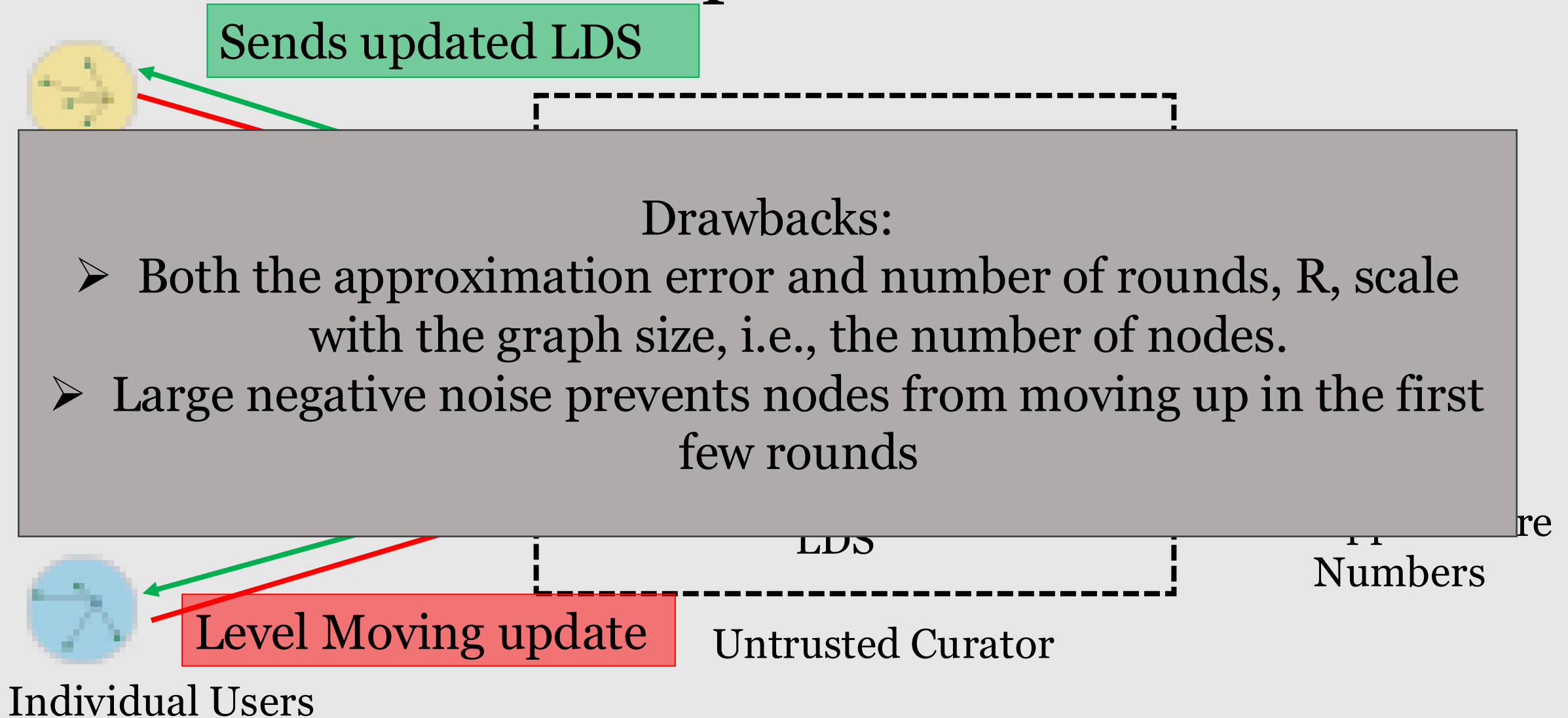
First Private k-Core Implementation



k-Core Decomposition



LEDP k-Core Decomposition



k-CoreD Algorithm

Degree Thresholding

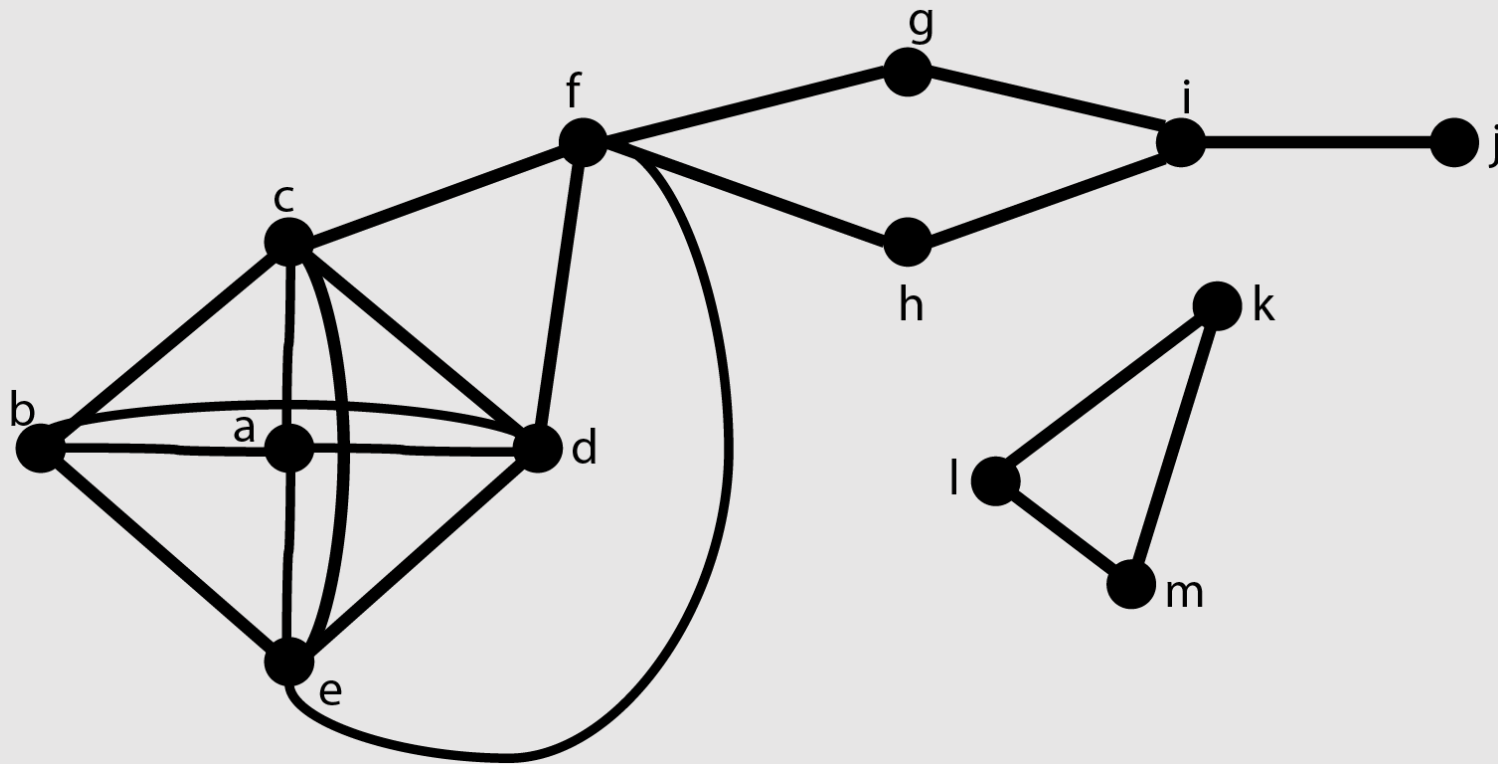
Each node computes a threshold value based on its noisy degree, that determines the max number of rounds the node participates in. Thus, the number of rounds

$R \sim \max(\text{degree-thresholds})$

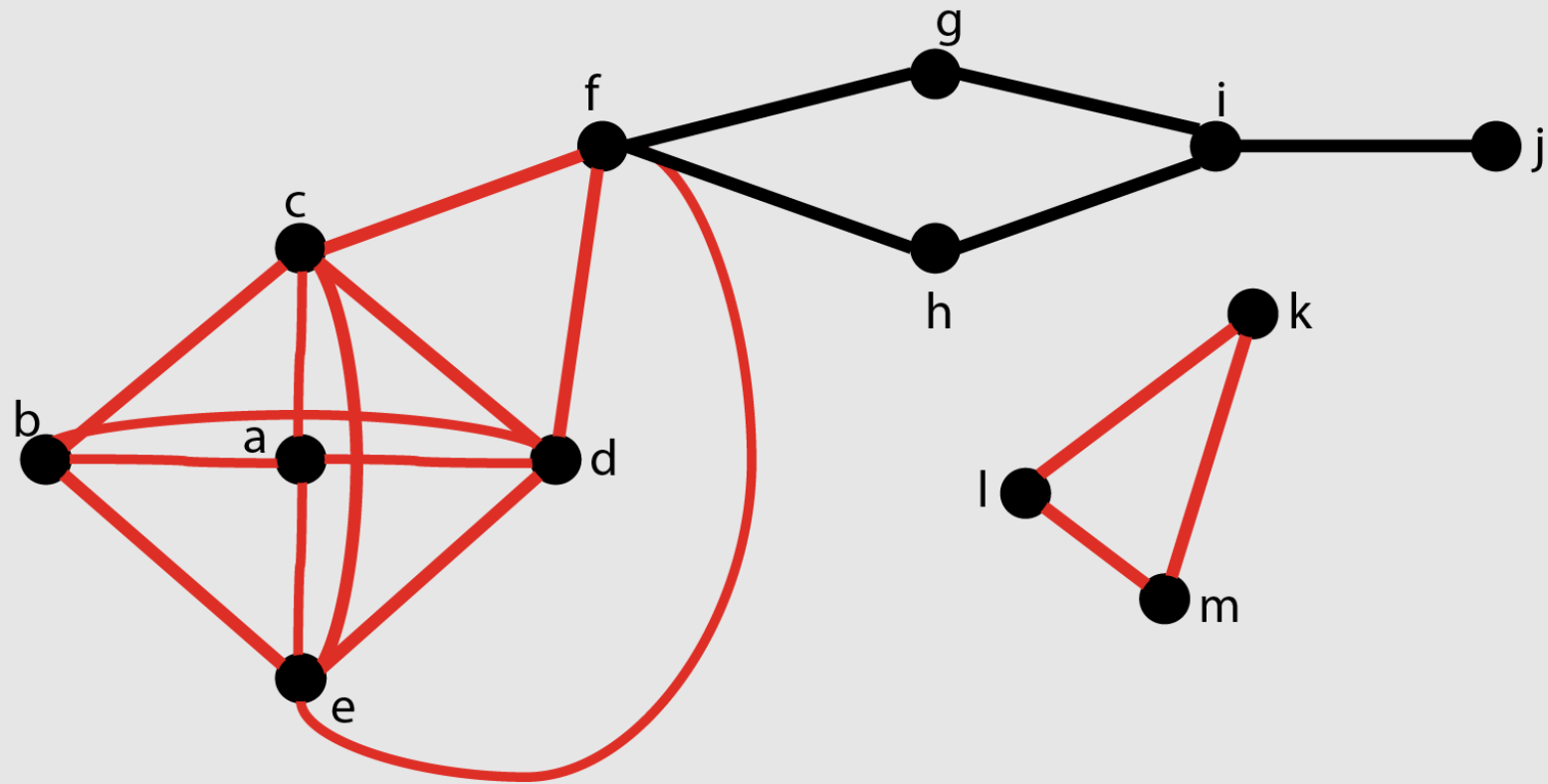
Bias Terms

We use analytically derived bias terms based on the standard deviation of the symmetric geometric distribution to account for the case when large positive or negative noise is drawn

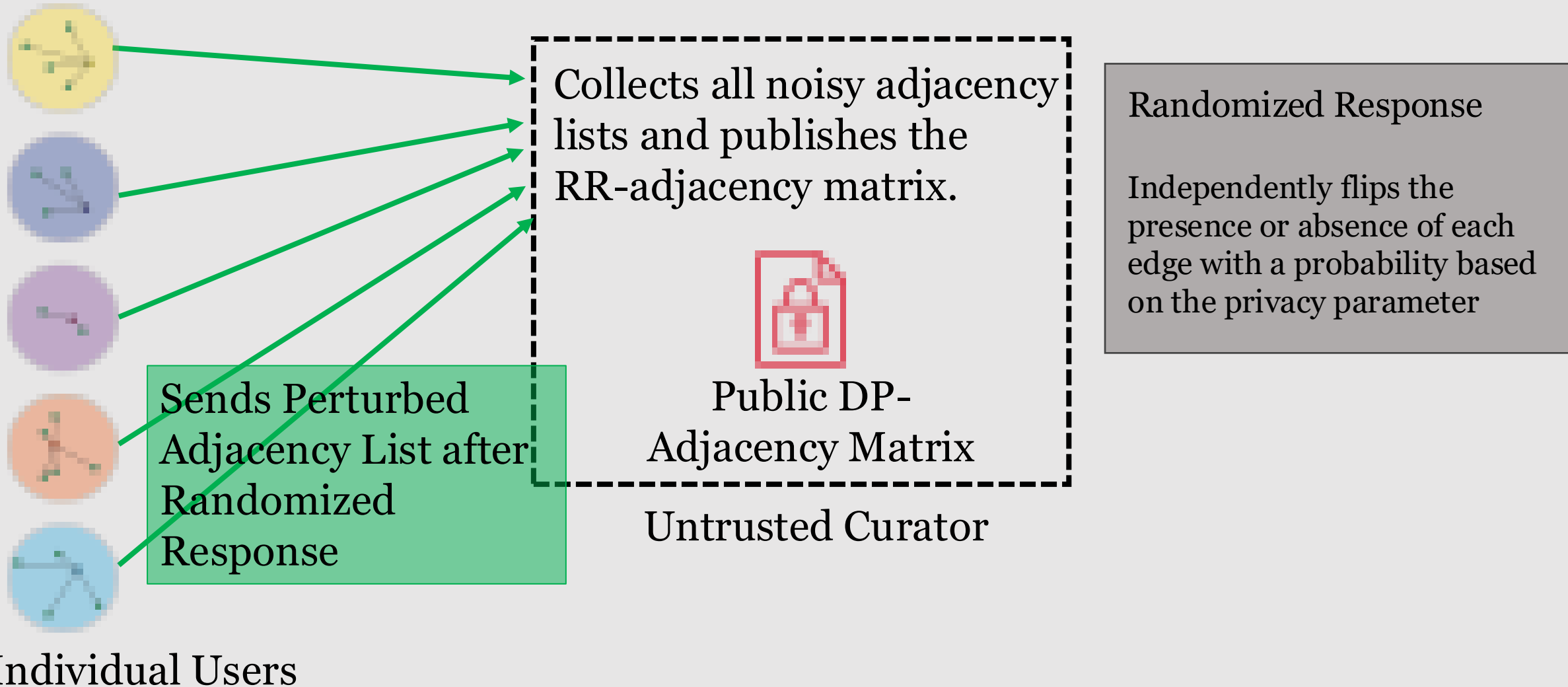
Triangle Counting



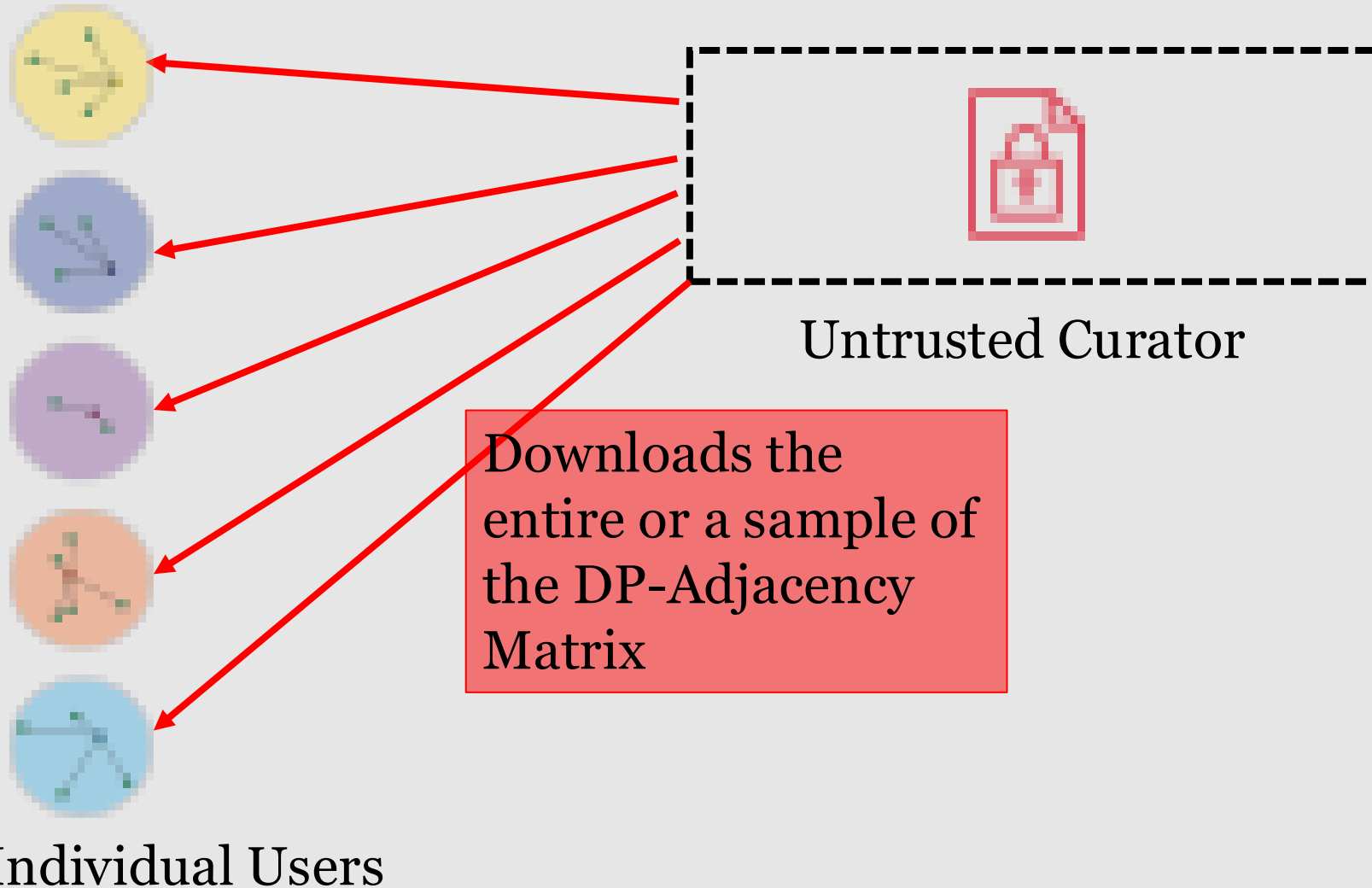
Triangle Counting



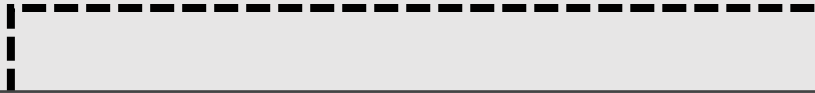
LEDP Triangle Counting



LEDP Triangle Counting



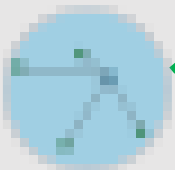
LEDP Triangle Counting



Drawbacks:

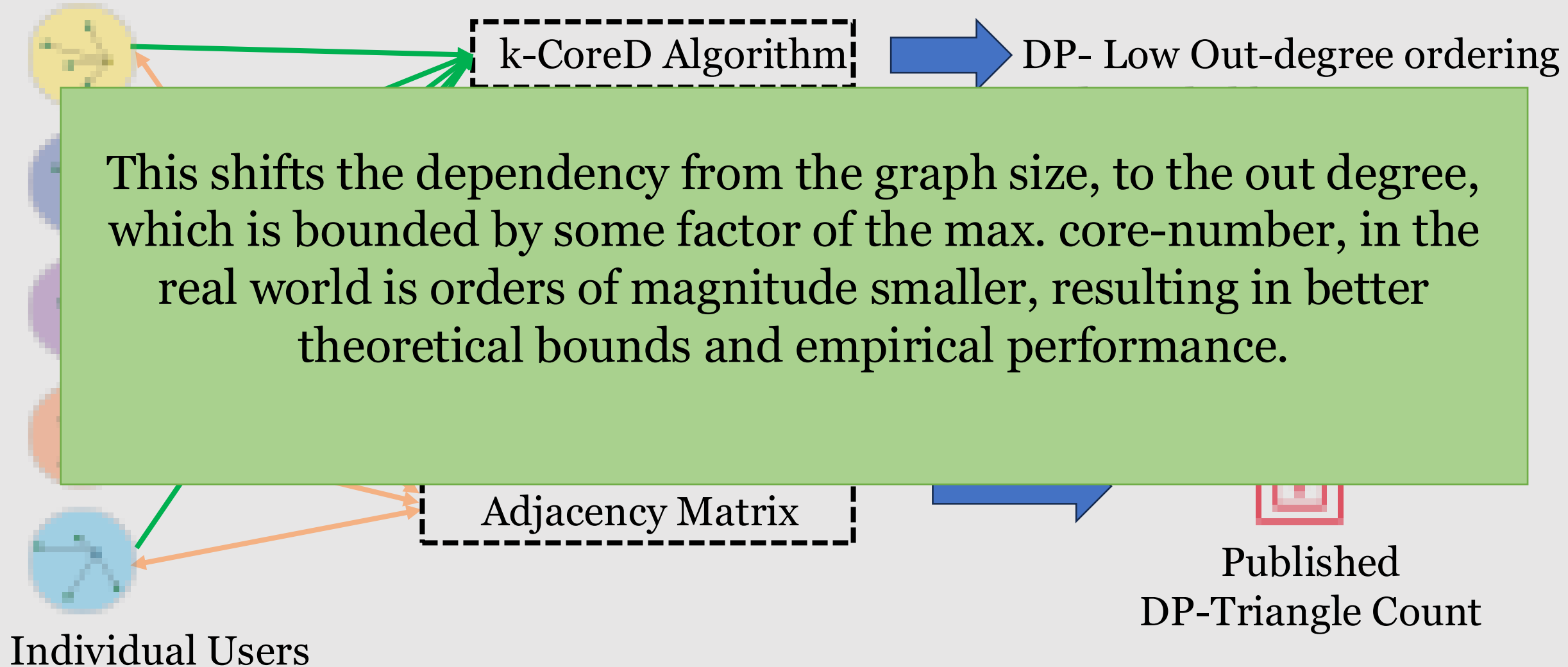
- Relies on either all or a sample of edges after RR
 - Error Bounds scale poorly with graph size

counts



Individual Users

EdgeOrient _{Δ}



Experimental Evaluation

Datasets

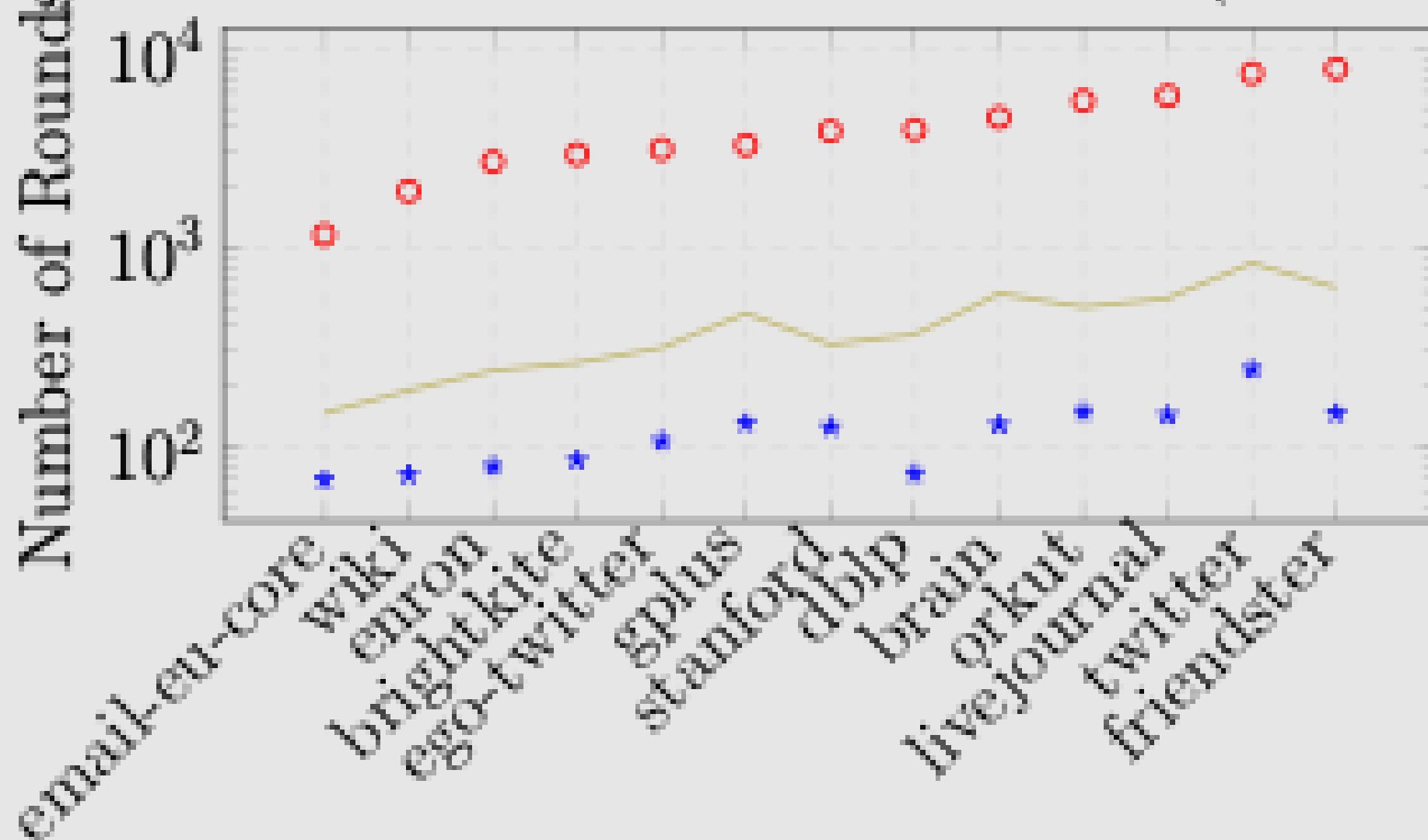
Name	Num. Vertices	Num. Edges	Max Degree	Max. Core Num.	Num. Triangles
email-eu-core	986	1,329,336	345	34	105,461
wiki	7115	100,761	1065	35	608,387
enron	36,692	183,830	1383	43	727,044
brightkite	58,228	214,078	1134	52	494,728
ego-twitter	81,306	1,342,296	3383	96	13,082,506
gplus	107,614	12,238,235	20,127	752	1,073,677,742
stanford	281,903	1,992,635	38,625	71	11,329,473
dblp	317,080	1,049,866	343	113	2,224,385
brain	784, 262	267,844,669	21,743	1200	
orkut	3,072,441	117,185,083	33,313	253	
livejournal	4,846,609	42,851,237	20,333	372	
twitter	41,652,230	1,202,513,046	2,997,487	2488	
friendster	65,608,366	1,806,067,135	5214	304	

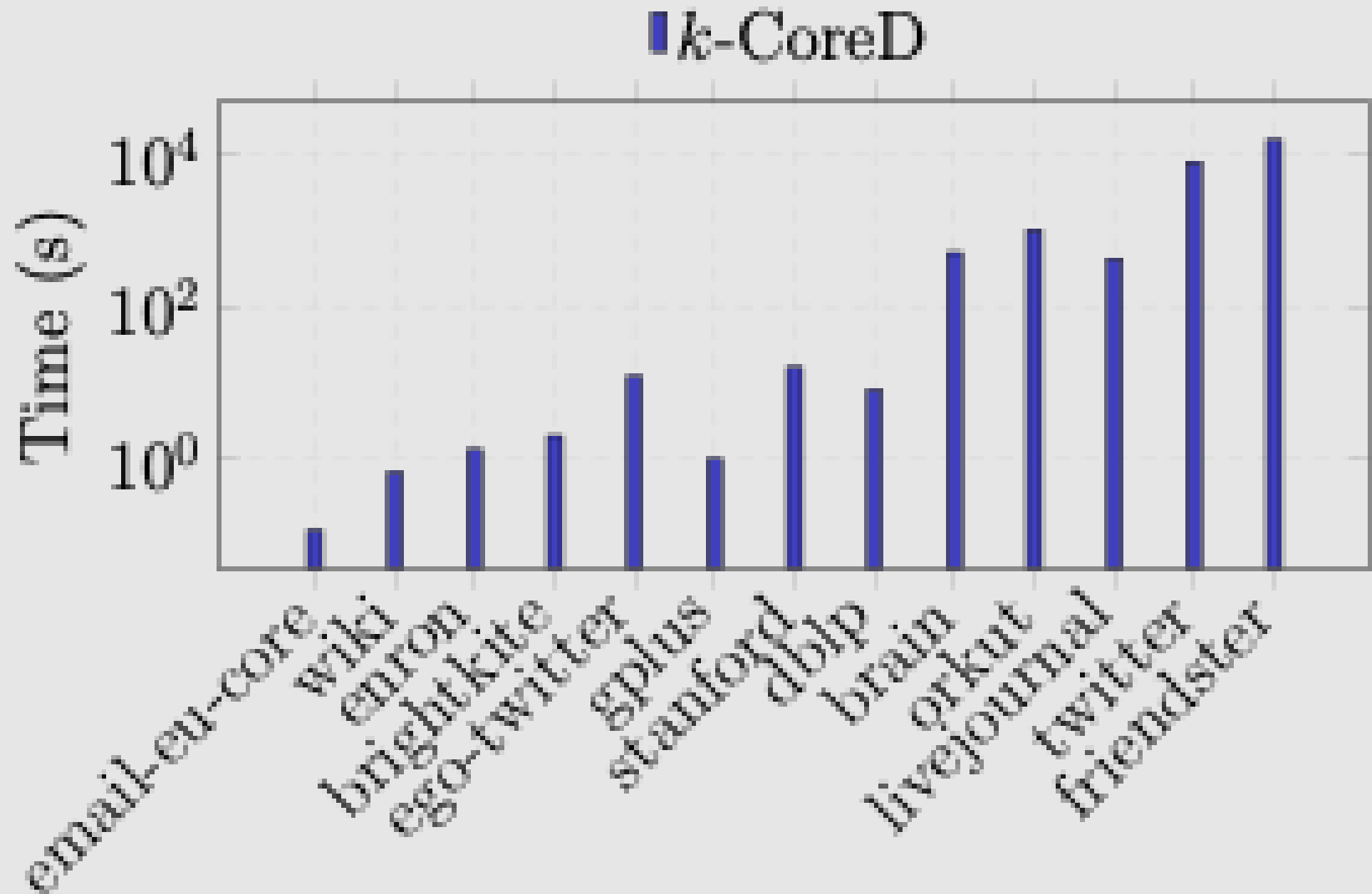
Setup

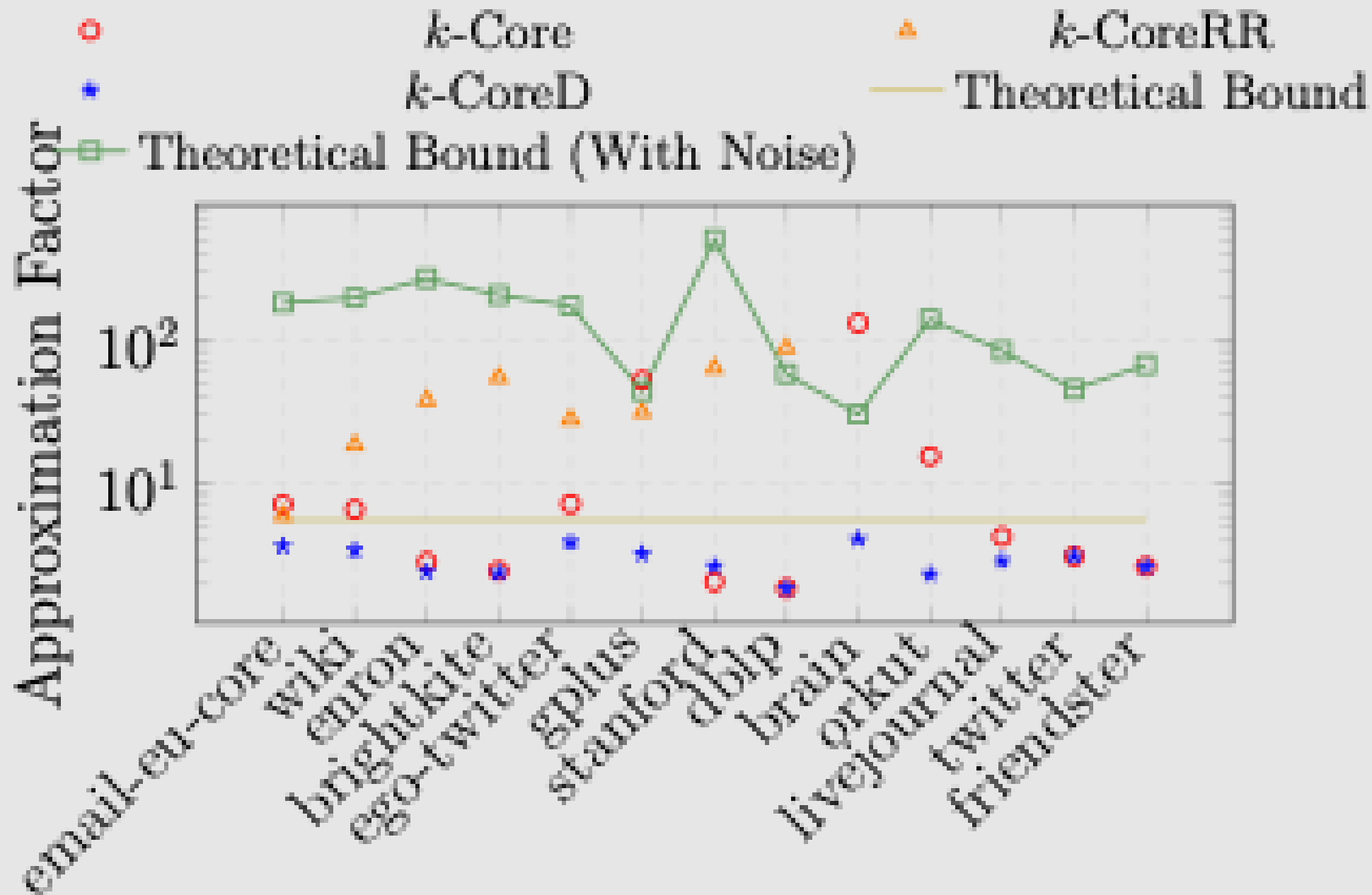
- Compute Resources: We use a Google Cloud c3-standard-176-instance with 88 physical cores, and disable hyperthreading
- Baselines:
 - We implement naïve RR based baselines
 - For k-Core Decomposition we implement the SOTA
 - For Triangle Counting we compare against the SOTA
- Parameters:
 - Epsilon (Privacy Parameter) = 1.0
 - Wall-Clock Limit Per Run = 4 hours
- Error Metric:

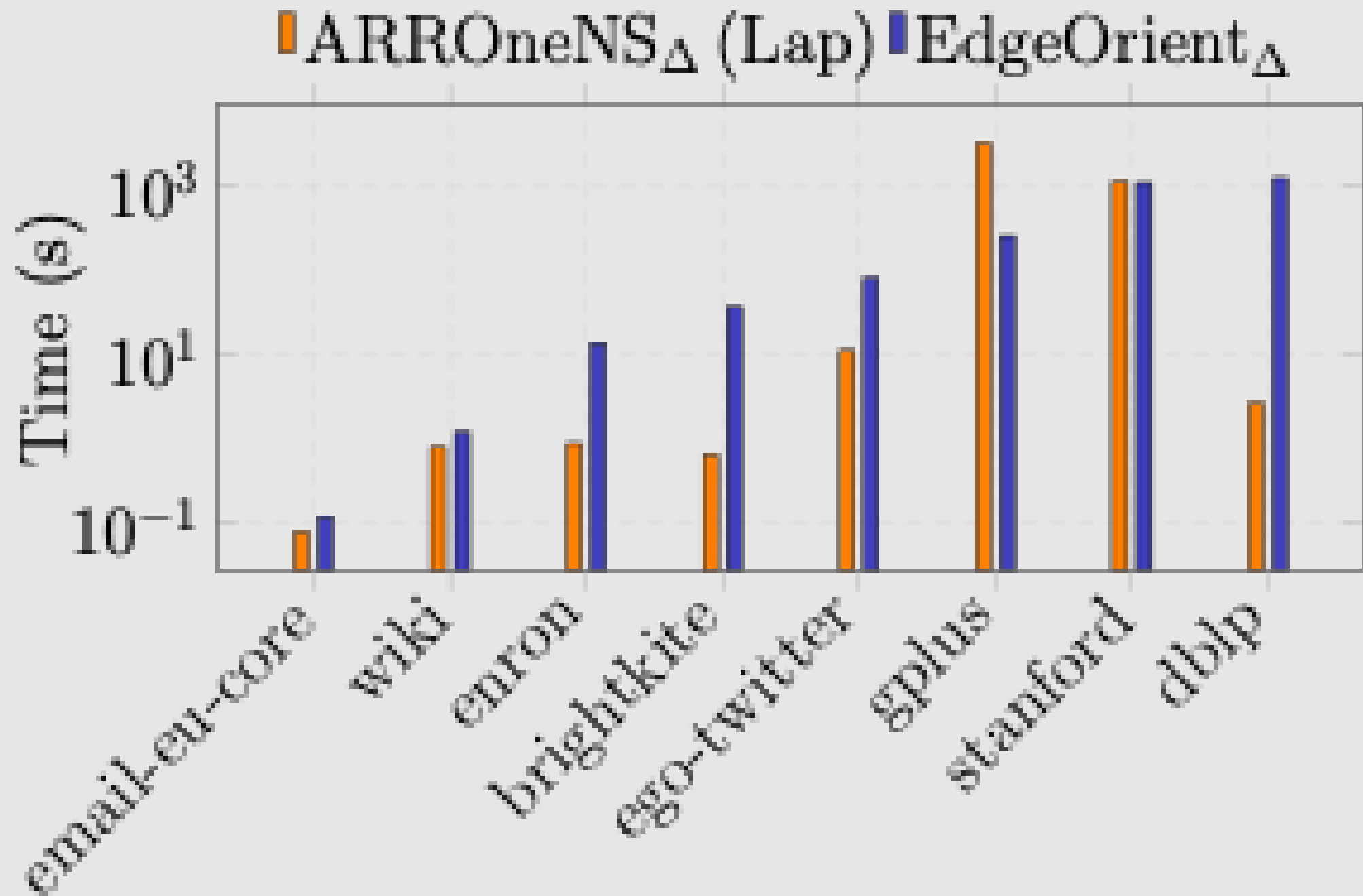
$$Approx. Factor = \frac{\max(\hat{k}, k)}{\min(\hat{k}, k)}$$

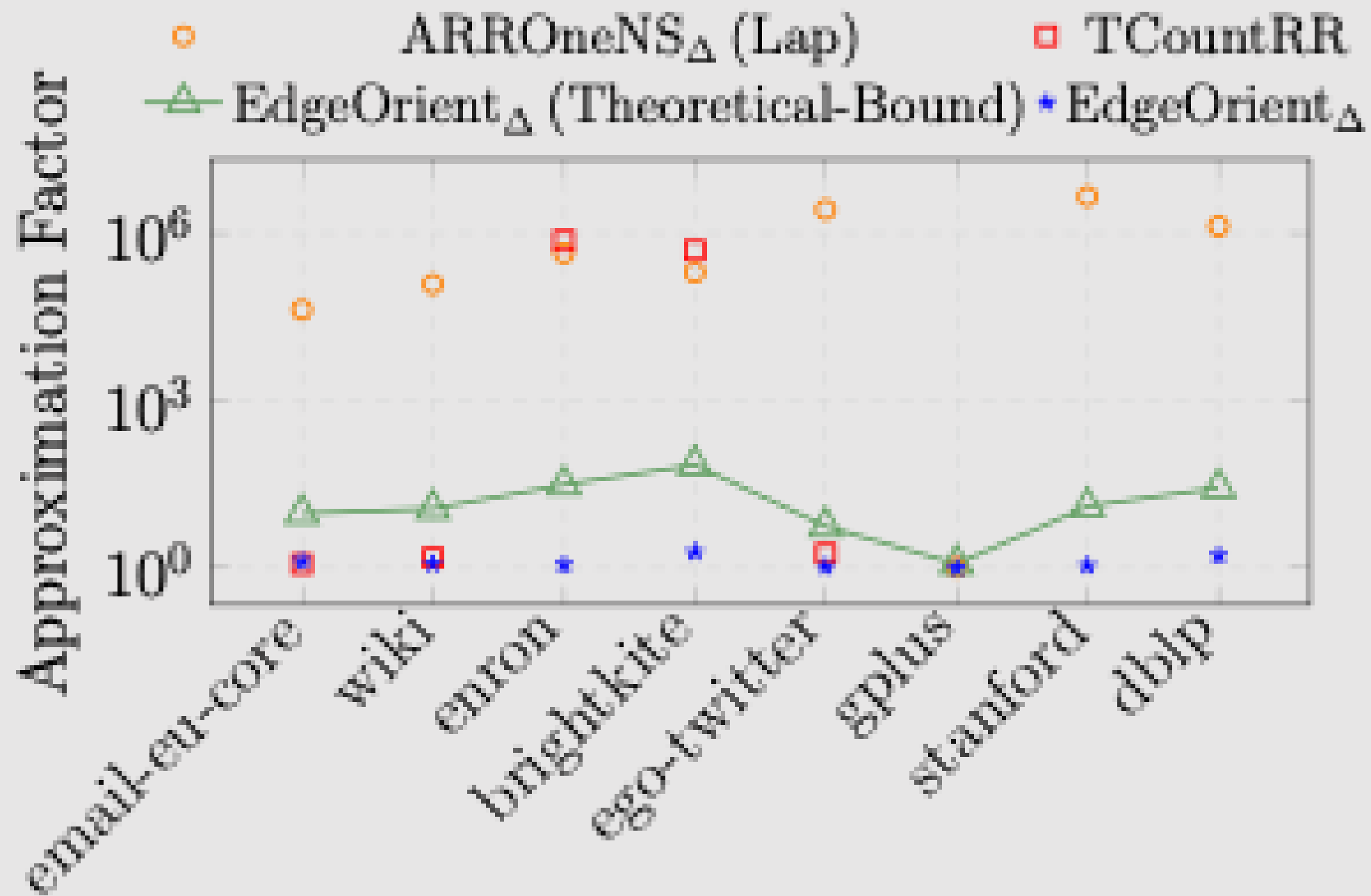
○ k -Core
 ★ k -CoreD
 — Theoretical Bound (Without Noise)











Thank You & Questions



Code



Full Paper