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On the informational structure in optimal dynamic stochastic control¹

Matija Vidmar (joint work with S. D. Jacka (Warwick))

VeSFiM seminar, UL FMF

March, 2015

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On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

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Motivation

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- is random; the objective being to maximize/minimize its expectation;
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Motivation (cont'd)

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Motivation (cont'd)

Major question # 1:

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

Matija Vidmar

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Motivation (cont'd)

Major question # 1: Can we offer a consistent general framework for optimal dynamic stochastic control, with an explicit control-dependent informational structure, and that comes equipped with an abstract version of Bellman's optimality (/super/martingale) principle?

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Motivation (cont'd)

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Motivation (cont'd)

Key ingredient is the modeling of information:

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If two controls agree up to a certain time, then what we have observed up to that time should also agree.

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Key ingredient is the modeling of information:

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If two controls agree up to a certain time, then what we have observed up to that time should also agree.

 At the level of random (stopping) times, and in the context of (completed) natural filtrations of processes, this 'obvious' requirement becomes surprisingly non-trivial (at least in continuous time).

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Motivation (cont'd)

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Motivation (cont'd)

Major question # 2:

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Motivation (cont'd)

Major question # 2: If X and Y are two processes, and S a stopping time of both (enough one?) of their (possibly completed) natural filtrations, with the stopped processes agreeing, $X^S = Y^S$ (possibly only with probability one), must the two (completed) natural filtrations *at* the time S agree also?

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Literature overview

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Literature overview

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Literature overview

• On the 'optimal dynamic stochastic control' front:

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- On the 'optimal dynamic stochastic control' front:
 - Of course, the phenomenon *has* entered *and* been studied in the literature in specific situations/problems; but focus there on reducing (i.e. *a priori* proving a suitable equivalence of) the original control problem, which is based on *partial control-dependent observation*, to an associated *'separated'* problem, which is based on *complete observation*.

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 - As far as general frameworks go, however, hitherto, only a single, non-control dependent (observable) informational flow appears to have been allowed.

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- On the 'informational consistency' front:
 - \blacksquare What is essentially required is a kind-of Galmarino's test "connecting $\sigma(X^S)$ with $\mathcal{F}^{X^{\prime\prime}}_S$.

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 - In literature this is available for coordinate processes on canonical spaces.

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 - \blacksquare What is essentially required is a kind-of Galmarino's test "connecting $\sigma(X^S)$ with $\mathcal{F}^{X^n}_S.$
 - In literature this is available for coordinate processes on canonical spaces.
 - O However, coordinate processes are quite restrictive, and certainly not pertinent to stochastic control ...

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Informal statement of results

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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• Basically: we answer to the affirmative the two major questions posed above (and several related ones, in the process).

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- Basically: we answer to the affirmative the two major questions posed above (and several related ones, in the process).
- Specifically:

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- Basically: we answer to the affirmative the two major questions posed above (and several related ones, in the process).
- Specifically:
 - Addressing the first question, there is put forward a general stochastic control framework which explicitly allows for a control-dependent informational flow. In particular, there is provided a fully general (modulo the relevant (technical) condition) abstract version of Bellman's principle in such a setting.

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- Basically: we answer to the affirmative the two major questions posed above (and several related ones, in the process).
- Specifically:
 - Addressing the first question, there is put forward a general stochastic control framework which explicitly allows for a control-dependent informational flow. In particular, there is provided a fully general (modulo the relevant (technical) condition) abstract version of Bellman's principle in such a setting.
 - With respect to the second question, a generalization of (a part of) Galmarino's test to a non-canonical space setting is proved, although full generality could not be achieved. Several corollaries and related findings are given, which in particular shed light on the theme of 'informational consistency' (at random /stopping/ times).

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Part I: Dynamic stochastic control with control-dependent information

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Part I: Dynamic stochastic control with control-dependent information

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The second 'probabilistic' approach – of complete filtrations – will be dealt with in parallel to the default first – 'measure-theoretic' – setting. Any differences of the second approach as compared to the first, will be put in $\{\}$ braces.

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An abstract stochastic control system

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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An abstract stochastic control system

We will see a system of stochastic control as consisting of:

 $(T, \mathbf{C}, \Omega, (\mathcal{F}^c)_{c \in \mathbf{C}}, (\mathsf{P}^c)_{c \in \mathbf{C}}, J, (\mathcal{G}^c)_{c \in \mathbf{C}})$

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(i) A set T with a linear ordering \leq . We assume (for simplicity) either $T = \mathbb{N}_0$, or else $T = [0, \infty)$, with the usual order. T is the *time set*.

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- (iii) A set Ω endowed with a collection of σ-algebras (F^c)_{c∈C}. Ω is the sample space and F^c is all the *information accumulated* by the "end of time" / a "terminal time", when c is the chosen control.

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- (iv) $(\mathsf{P}^c)_{c \in \mathbf{C}}$, a collection of {complete} probability measures, each P^c having domain which includes the { P^c -complete} σ -field \mathcal{F}^c (for $c \in \mathbf{C}$).

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- (iii) A set Ω endowed with a collection of σ-algebras (F^c)_{c∈C}. Ω is the sample space and F^c is all the *information accumulated* by the "end of time" / a "terminal time", when c is the chosen control.
- (iv) $(\mathsf{P}^c)_{c \in \mathbf{C}}$, a collection of {complete} probability measures, each P^c having domain which includes the { P^c -complete} σ -field \mathcal{F}^c (for $c \in \mathbf{C}$).
- (v) A function $J: \mathbf{C} \to [-\infty, +\infty]^{\Omega}$, each J(c) being \mathcal{F}^c measurable (as c runs over \mathbf{C}) {and defined up to P^c -a.s. equality}. We further insist $\mathsf{E}^{\mathsf{P}^c}J(c)^- < \infty$ for all $c \in \mathbf{C}$. Given the control $c \in \mathbf{C}$, J(c) is the random payoff.

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Part I: Dynamic stochastic control with controldependent information Part II: Stopping times, stopped processes and natural filtrations at stopping times 00000000

An abstract stochastic control system ...

We will see a system of stochastic control as consisting of:

 $(T, \mathbf{C}, \Omega, (\mathcal{F}^c)_{c \in \mathbf{C}}, (\mathsf{P}^c)_{c \in \mathbf{C}}, J, (\mathcal{G}^c)_{c \in \mathbf{C}})$

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- (vi) A collection of filtrations $(\mathcal{G}^c)_{c \in \mathbf{C}}$ on Ω . It is assumed $\mathcal{G}^c_{\infty} := \bigvee_{t \in T} \mathcal{G}^c_t \subset \mathcal{F}^c$, and (for simplicity) that \mathcal{G}^c_0 is P^c -trivial (for all $c \in \mathbf{C}$) {and contains all the P^c -null sets}, while $\mathcal{G}^c_0 = \mathcal{G}^d_0$ {i.e. the null sets for P^c and P^d are the same} and $\mathsf{P}^c|_{\mathcal{G}^c_0} = \mathsf{P}^d|_{\mathcal{G}^d_0}$ for all $\{c, d\} \subset \mathbf{C}$. \mathcal{G}^c_t is the *information acquired* by the controller by time $t \in T$, if the control chosen is $c \in \mathbf{C}$.

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... its dynamical structure ...

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

... its dynamical structure ...

We will consider furthermore given a collection G of controlled times,

Part II: Stopping times, stopped processes and natural filtrations at stopping times

... its dynamical structure ...

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Definition (Controlled times)

A collection of random times $S = (S^c)_{c \in \mathbf{C}}$ is called a **controlled time**, if S^c is a {defined up to P^c -a.s. equality} stopping time of \mathcal{G}^c for every $c \in \mathbf{C}$.

Part II: Stopping times, stopped processes and natural filtrations at stopping times

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

... its dynamical structure ...

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(1)
$$c \in \mathcal{D}(c, S)$$
 for all $(c, S) \in \mathbf{C} \times \mathbf{G}$.

- (2) For all $\mathcal{S} \in \mathbf{G}$ and $\{c, d\} \subset \mathbf{C}$, $d \in \mathcal{D}(c, \mathcal{S})$ implies $\mathcal{S}^c = \mathcal{S}^d$ {P^c & P^d-a.s}.
- (3) If $\{S, \mathcal{T}\} \subset \mathbf{G}, c \in \mathbf{C}$ and $S^c = \mathcal{T}^c \{\mathsf{P}^c\text{-a.s}\}$, then $\mathcal{D}(c, S) = \mathcal{D}(c, \mathcal{T})$.
- (4) If $\{S, T\} \subset \mathbf{G}$ and $c \in \mathbf{C}$ for which $S^d \leq T^d \{\mathsf{P}^d\text{-a.s.}\}$ for $d \in \mathcal{D}(c, T)$, then $\mathcal{D}(c, T) \subset \mathcal{D}(c, S)$.
- (5) For each $S \in \mathbf{G}$, $\{\mathcal{D}(c, S) : c \in \mathbf{C}\}$ is a partition of $\mathbf{C} (\rightarrow$ denote the induced equivalence relation by \sim_{S}).
- (6) For all $(c, S) \in \mathbf{C} \times \mathbf{G}$: $\mathcal{D}(c, S) = \{c\}$ (resp. $\mathcal{D}(c, S) = \mathbf{C}$), if S^c is identically {or P^c -a.s.} equal to ∞ (resp. 0).

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... temporal consisteny and optimality

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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... temporal consisteny and optimality

Assumption (Temporal consistency)

For all $\{c, d\} \subset \mathbf{C}$ and $S \in \mathbf{G}$ satisfying $c \sim_S d$, we have $\mathcal{G}_{S^c}^c = \mathcal{G}_{S^d}^d$ and $\mathsf{P}^c|_{\mathcal{G}_{S^c}^c} = \mathsf{P}^d|_{\mathcal{G}_{S^d}^d}$.

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Definition (Optimal expected payoff)

We define $v := \sup_{c \in \mathbf{C}} \mathsf{E}^{\mathsf{P}^c} J(c)$ (sup $\emptyset := -\infty$), the **optimal expected payoff**. Next, $c \in \mathbf{C}$ is said to be **optimal** if $\mathsf{E}^{\mathsf{P}^c} J(c) = v$. Finally, a **C**-valued net is said to be **optimizing** if its limit is v.

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The conditional payoff and the Bellman system

The conditional payoff and the Bellman system

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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The conditional payoff and the Bellman system

Definition (Conditional payoff & Bellman system)

We define for $c \in \mathbf{C}$ and $\mathcal{S} \in \mathbf{G}$:

$$J(c,\mathcal{S}) := \mathsf{E}^{\mathsf{P}^c}[J(c)|\mathcal{G}^c_{\mathcal{S}^c}],$$

and then

$$V(c,\mathcal{S}) := \mathsf{P}^{c}|_{\mathcal{G}^{c}_{\mathcal{S}^{c}}}\text{-}\mathrm{esssup}_{d\in\mathcal{D}(c,\mathcal{S})}J(d,\mathcal{S});$$

and say $c \in \mathbf{C}$ is conditionally optimal at $\mathcal{S} \in \mathbf{G}$, if $V(c, \mathcal{S}) = J(c, \mathcal{S})$ P^c -a.s. $(J(c, \mathcal{S}))_{(c, \mathcal{S}) \in \mathbf{C} \times \mathbf{G}}$ is called the conditional payoff system and $(V(c, \mathcal{S}))_{(c, \mathcal{S}) \in \mathbf{C} \times \mathbf{G}}$ the Bellman system.

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A 'technical' condition

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A 'technical' condition

Proposition

Let $c \in \mathbf{C}$, $S \in \mathbf{G}$ and $\epsilon \in [0, \infty)$, $M \in (0, \infty]$. Then $(1) \Rightarrow (2) \Rightarrow (3)$.

- (1) (i) For all $d \in \mathcal{D}(c, S)$, $\mathsf{P}^d = \mathsf{P}^c$. AND (ii) For all $\{d, d'\} \subset \mathcal{D}(c, S)$ and $G \in \mathcal{G}^c_{S^c}$, there is a $d'' \in \mathcal{D}(c, S)$ such that $J(d'') \ge M \land [\mathbb{1}_G J(d) + \mathbb{1}_{\Omega \setminus G} J(d')] - \epsilon \mathsf{P}^c$ -a.s.
- (2) For all $\{d, d'\} \subset \mathcal{D}(c, \mathcal{S})$ and $G \in \mathcal{G}^{c}_{\mathcal{S}^{c}}$, there is a $d'' \in \mathcal{D}(c, \mathcal{S})$ such that $J(d'', \mathcal{S}) \geq M \wedge [\mathbb{1}_{G}J(d, \mathcal{S}) + \mathbb{1}_{\Omega \setminus G}J(d', \mathcal{S})] \epsilon \mathsf{P}^{c}$ -a.s.
- (3) $(J(d, S))_{d \in \mathcal{D}(c,S)}$ has the " (ϵ, M) -upwards lattice property": For all $\{d, d'\} \subset \mathcal{D}(c, S)$ there exists a $d'' \in \mathcal{D}(c, S)$ such that

$$J(d'',\mathcal{S}) \ge (M \land J(d,\mathcal{S})) \lor (M \land J(d',\mathcal{S})) - \epsilon$$

P^c-a.s.

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A 'technical' condition (cont'd)

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A 'technical' condition (cont'd)

Assumption (Upwards lattice property)

For all $c \in \mathbf{C}$, $S \in \mathbf{G}$ and $\{\epsilon, M\} \subset (0, \infty)$, $(J(d, S))_{d \in \mathcal{D}(c, S)}$ enjoys the (ϵ, M) -upwards lattice property.

Part II: Stopping times, stopped processes and natural filtrations at stopping times

A 'technical' condition (cont'd)

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A 'technical' condition (cont'd)

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This is only seemingly of merely a 'technical' nature In fact, it represents a direct linking between C, G and the collection $(\mathcal{G}^c)_{c \in \mathbf{C}}$.

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A 'technical' condition (cont'd)

Assumption (Upwards lattice property)

For all $c \in \mathbf{C}$, $S \in \mathbf{G}$ and $\{\epsilon, M\} \subset (0, \infty)$, $(J(d, S))_{d \in \mathcal{D}(c, S)}$ enjoys the (ϵ, M) -upwards lattice property.

This is only seemingly of merely a 'technical' nature In fact, it represents a direct linking between C, G and the collection $(\mathcal{G}^c)_{c\in \mathbf{C}}$. In particular, it may fail at deterministic times!!

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Super/-/sub-martingale systems

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Super/-/sub-martingale systems

Definition ((C, G)-super/-/sub-martingale systems)

A collection $X = (X(c, S))_{(c,S)\in(\mathbf{C},\mathbf{G})}$ of functions from $[-\infty, +\infty]^{\Omega}$ is a (\mathbf{C}, \mathbf{G}) - (resp. **super**-, **sub**-) **martingale system**, if for each $(c, S) \in \mathbf{C} \times \mathbf{G}$ (i) X(c, S) is $\mathcal{G}^c_{S^c}$ -measurable, (ii) X(c, S) = X(d, S) \mathbf{P}^c -a.s. and \mathbf{P}^d -a.s., whenever $c \sim_S d$, (iii) (resp. the negative, positive part of) X(c, S) is integrable and (iv) for all $\{S, \mathcal{T}\} \subset \mathbf{G}$ and $c \in \mathbf{C}$ with $S^d \leq \mathcal{T}^d$ {P^d-a.s.} for $d \in \mathcal{D}(c, \mathcal{T})$,

$$\mathsf{E}^{\mathsf{P}^{c}}[X(c,\mathcal{T})|\mathcal{G}^{c}_{\mathcal{S}^{c}}] = X(c,\mathcal{S})$$

 $\left(\text{resp. } \mathsf{E}^{\mathsf{P}^c}[X(c,\mathcal{T})|\mathcal{G}^c_{\mathcal{S}^c}] \leq X(c,\mathcal{S}), \, \mathsf{E}^{\mathsf{P}^c}[X(c,\mathcal{T})|\mathcal{G}^c_{\mathcal{S}^c}] \geq X(c,\mathcal{S})\right) \, \mathsf{P}^c\text{-a.s.}$

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Part I: Dynamic stochastic control with controldependent information Part II: Stopping times, stopped processes and natural filtrations at stopping times

Bellman's principle

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Bellman's principle

Theorem (Bellman's principle)

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Bellman's principle

Theorem (Bellman's principle)

 $(V(c, S))_{(c,S)\in \mathbf{C}\times\mathbf{G}}$ is a (\mathbf{C}, \mathbf{G}) -supermartingale system. Moreover, if $c^* \in \mathbf{C}$ is optimal, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ has a constant \mathbf{P}^{c^*} -expectation (equal to the optimal value $v = \mathbf{E}^{\mathbf{P}^{c^*}} J(c^*)$). If further $\mathbf{E}^{\mathbf{P}^{c^*}} J(c^*) < \infty$, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ is a **G**-martingale in the sense that (i) for each $\mathcal{T} \in \mathbf{G}$, $V(c^*, \mathcal{T})$ is $\mathcal{G}_{\mathcal{T}^{c^*}}^{c^*}$ -measurable and \mathbf{P}^{c^*} -integrable and (ii) for any $\{\mathcal{S},\mathcal{T}\} \subset \mathbf{G}$ with $\mathcal{S}^d \leq \mathcal{T}^d \{\mathbf{P}^d$ -a.s.} for $d \in \mathcal{D}(c^*, \mathcal{T})$, \mathbf{P}^{c^*} -a.s.,

$$\mathsf{E}^{\mathsf{P}^{c^*}}[V(c^*,\mathcal{T})|\mathcal{G}^{c^*}_{\mathcal{S}^{c^*}}] = V(c^*,\mathcal{S}).$$

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Part I: Dynamic stochastic control with controldependent information Part II: Stopping times, stopped processes and natural filtrations at stopping times

Bellman's principle

Theorem (Bellman's principle)

 $(V(c, S))_{(c,S)\in \mathbf{C}\times\mathbf{G}}$ is a (\mathbf{C}, \mathbf{G}) -supermartingale system. Moreover, if $c^* \in \mathbf{C}$ is optimal, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ has a constant \mathbf{P}^{c^*} -expectation (equal to the optimal value $v = \mathbf{E}^{\mathbf{P}^{c^*}} J(c^*)$). If further $\mathbf{E}^{\mathbf{P}^{c^*}} J(c^*) < \infty$, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ is a **G**-martingale in the sense that (i) for each $\mathcal{T} \in \mathbf{G}$, $V(c^*, \mathcal{T})$ is $\mathcal{G}_{\mathcal{T}^{c^*}}^{c^*}$ -measurable and \mathbf{P}^{c^*} -integrable and (ii) for any $\{\mathcal{S},\mathcal{T}\} \subset \mathbf{G}$ with $\mathcal{S}^d \leq \mathcal{T}^d \{\mathbf{P}^d$ -a.s.} for $d \in \mathcal{D}(c^*, \mathcal{T})$, \mathbf{P}^{c^*} -a.s.,

$$\mathsf{E}^{\mathsf{P}^{c^*}}[V(c^*,\mathcal{T})|\mathcal{G}^{c^*}_{\mathcal{S}^{c^*}}] = V(c^*,\mathcal{S}).$$

Furthermore, if $c^* \in \mathbf{C}$ is conditionally optimal at $S \in \mathbf{G}$ and $\mathbf{E}^{\mathbf{P}c^*} J(c^*) < \infty$, then c^* is conditionally optimal at \mathcal{T} for any $\mathcal{T} \in \mathbf{G}$ satisfying $\mathcal{T}^d \geq S^d \{\mathbf{P}^d\text{-a.s.}\}$ for $d \in \mathcal{D}(c^*, \mathcal{T})$. In particular, if c^* is optimal, then it is conditionally optimal at 0, so that if further $\mathbf{E}^{\mathbf{P}c^*} J(c^*) < \infty$, then c^* must be conditionally optimal at any $S \in \mathbf{G}$.

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Part I: Dynamic stochastic control with controldependent information Part II: Stopping times, stopped processes and natural filtrations at stopping times

Bellman's principle

Theorem (Bellman's principle)

 $(V(c, S))_{(c,S)\in \mathbf{C}\times\mathbf{G}}$ is a (\mathbf{C}, \mathbf{G}) -supermartingale system. Moreover, if $c^* \in \mathbf{C}$ is optimal, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ has a constant \mathbf{P}^{c^*} -expectation (equal to the optimal value $v = \mathbf{E}^{\mathbf{P}^{c^*}} J(c^*)$). If further $\mathbf{E}^{\mathbf{P}^{c^*}} J(c^*) < \infty$, then $(V(c^*, \mathcal{T}))_{\mathcal{T}\in\mathbf{G}}$ is a **G**-martingale in the sense that (i) for each $\mathcal{T} \in \mathbf{G}$, $V(c^*, \mathcal{T})$ is $\mathcal{G}_{\mathcal{T}^{c^*}}^{c^*}$ -measurable and \mathbf{P}^{c^*} -integrable and (ii) for any $\{\mathcal{S},\mathcal{T}\} \subset \mathbf{G}$ with $\mathcal{S}^d \leq \mathcal{T}^d \{\mathbf{P}^d$ -a.s.} for $d \in \mathcal{D}(c^*, \mathcal{T})$, \mathbf{P}^{c^*} -a.s.,

$$\mathsf{E}^{\mathsf{P}^{c^*}}[V(c^*,\mathcal{T})|\mathcal{G}^{c^*}_{\mathcal{S}^{c^*}}] = V(c^*,\mathcal{S}).$$

Furthermore, if $c^* \in \mathbf{C}$ is conditionally optimal at $S \in \mathbf{G}$ and $\mathbf{E}^{\mathbf{p}^{c^*}} J(c^*) < \infty$, then c^* is conditionally optimal at \mathcal{T} for any $\mathcal{T} \in \mathbf{G}$ satisfying $\mathcal{T}^d \geq S^d \{\mathsf{P}^d\text{-a.s.}\}$ for $d \in \mathcal{D}(c^*, \mathcal{T})$. In particular, if c^* is optimal, then it is conditionally optimal at 0, so that if further $\mathbf{E}^{\mathbf{p}^{c^*}} J(c^*) < \infty$, then c^* must be conditionally optimal at any $S \in \mathbf{G}$. Conversely, and regardless of whether the "upwards lattice assumption" holds true, if \mathbf{G} includes a sequence $(S_n)_{n \in \mathbb{N}_0}$ for which (i) $S_0 = 0$, (ii) the family $(V(c^*, S_n))_{n \geq 0}$ has a constant \mathbf{P}^{c^*} -expectation and is uniformly integrable, and (iii) $V(c^*, S_n) \to V(c^*, \infty)$, \mathbf{P}^{c^*} -a.s. (or even just in \mathbf{P}^{c^*} -probability), as $n \to \infty$, then c^* is optimal.

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

Introduction

Part I: Dynamic stochastic control with control-dependent information

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The measure-theoretic case Case with completions

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Introduction

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A bird's eye view

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability.

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability. One's naïve expectation/ "it must be true":

Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability. One's naïve expectation/ "it must be true":

If X is a process, and S a time, then S is a stopping time of \mathcal{F}^X , if and only if it is a stopping time of \mathcal{F}^{X^S} .

Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability. One's naïve expectation/ "it must be true":

If X is a process, and S a time, then S is a stopping time of \mathcal{F}^X , if and only if it is a stopping time of \mathcal{F}^{X^S} . When so, then $\mathcal{F}^X_S = \sigma(X^S)$.

Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability. One's naïve expectation/ "it must be true":

If X is a process, and S a time, then S is a stopping time of \mathcal{F}^X , if and only if it is a stopping time of \mathcal{F}^{X^S} . When so, then $\mathcal{F}^X_S = \sigma(X^S)$. In particular, if X and Y are two processes, and S is a stopping time of either \mathcal{F}^X or of \mathcal{F}^Y , with $X^S = Y^S$, then S is a stopping time of \mathcal{F}^X and \mathcal{F}^Y both, and $\mathcal{F}^X_S = \sigma(X^S) = \sigma(Y^S) = \mathcal{F}^Y_S$.

Part II: Stopping times, stopped processes and natural filtrations at stopping times

A bird's eye view

Start "measure-theoretically", no completions, no probability. One's naïve expectation/ "it must be true":

If X is a process, and S a time, then S is a stopping time of \mathcal{F}^X , if and only if it is a stopping time of \mathcal{F}^{X^S} . When so, then $\mathcal{F}^X_S = \sigma(X^S)$. In particular, if X and Y are two processes, and S is a stopping time of either \mathcal{F}^X or of \mathcal{F}^Y , with $X^S = Y^S$, then S is a stopping time of \mathcal{F}^X and \mathcal{F}^Y both, and $\mathcal{F}^X_S = \sigma(X^S) = \sigma(Y^S) = \mathcal{F}^Y_S$. Further, if $U \leq V$ are two stopping times of \mathcal{F}^X , X again being a process, then $\sigma(X^U) = \mathcal{F}^X_U \subset \mathcal{F}^X_V = \sigma(X^V)$.

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

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Part II: Stopping times, stopped processes and natural filtrations at stopping times

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What about if one "completes everything"? Then it's trickier ...

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The measure-theoretic case

Part I: Dynamic stochastic control with controldependent information 00000000

Part II: Stopping times, stopped processes and natural filtrations at stopping times

Tools

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Tools

Blackwell's Theorem. Let (Ω, \mathcal{F}) be a Blackwell space, \mathcal{G} a sub- σ -field of \mathcal{F} and \mathcal{S} a separable sub- σ -field of \mathcal{F} . Then $\mathcal{G} \subset \mathcal{S}$, if and only if every atom of \mathcal{G} is a union of atoms of \mathcal{S} . In particular, a \mathcal{F} -measurable real function g is \mathcal{S} -measurable, if and only if g is constant on every atom of \mathcal{S} .

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Lemma (Key lemma)

Let X be a process (on Ω , with time domain $T \in \{\mathbb{N}_0, [0, \infty)\}$ and values in (E, \mathcal{E})), S an \mathcal{F}^X -stopping time, $A \in \mathcal{F}_S^X$. If $X_t(\omega) = X_t(\omega')$ for all $t \in T$ with $t \leq S(\omega) \wedge S(\omega')$, then $S(\omega) = S(\omega')$, $X^S(\omega) = X^S(\omega')$ and $\mathbb{1}_A(\omega) = \mathbb{1}_A(\omega')$.

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The measure-theoretic case

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Key results - stopping times

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Key results - stopping times

Theorem (Stopping times)

Let X be a process (on Ω , with time domain $T \in \{\mathbb{N}_0, [0, \infty)\}$ and values in (E, \mathcal{E})), $S : \Omega \to T \cup \{\infty\}$ a time. If $T = \mathbb{N}_0$, or else if the conditions:

- (1) $\sigma(X|_{[0,t]})$ and $\sigma(X^{S \wedge t})$ are separable, $(\operatorname{Im} X|_{[0,t]}, \mathcal{E}^{\otimes [0,t]})$ and $(\operatorname{Im} X^{S \wedge t}, \mathcal{E}^{\otimes T}|_{\operatorname{Im} X^{S \wedge t}})$ Hausdorff for each $t \in [0, \infty)$.
- (2) X^S and X are both measurable with respect to a Blackwell σ -field \mathcal{G} on Ω .

are met, then the following statements are equivalent:

(i)
$$S$$
 is an \mathcal{F}^X -stopping time.

(ii) S is an \mathcal{F}^{X^S} -stopping time.

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The measure-theoretic case

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Key results – Galmarino's test

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Key results – Galmarino's test

Theorem (Generalized Galmarino's test)

Let X be a process (on Ω , with time domain $T \in \{\mathbb{N}_0, [0, \infty)\}$ and values in (E, \mathcal{E})), S an \mathcal{F}^X -stopping time. If $T = \mathbb{N}_0$, then $\sigma(X^S) = \mathcal{F}^X_S$. Moreover, if X^S is $\mathcal{F}^X_S / \mathcal{E}^{\otimes T}$ -measurable (in particular, if it is adapted to the stopped filtration $(\mathcal{F}^X_{t \wedge S})_{t \in T}$) and either one of the conditions:

- (1) $\mathrm{Im}X^S \subset \mathrm{Im}X$.
- (2) (a) (Ω, \mathcal{G}) is Blackwell for some σ -field $\mathcal{G} \supset \mathcal{F}_{\infty}^X$.
 - (b) $\sigma(X^S)$ is separable.
 - (c) $(\mathrm{Im} X^S, \mathcal{E}^{\otimes T}|_{\mathrm{Im} X^S})$ is Hausdorff.

is met, then the following statements are equivalent:

(i)
$$A \in \mathcal{F}_{S}^{X}$$
.
(ii) $\mathbb{1}_{A}$ is constant on every set on which X^{S} is constant and $A \in \mathcal{F}_{\infty}^{X}$.
(iii) $A \in \sigma(X^{S})$.

The measure-theoretic case

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Key results - informational consistency

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

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Key results - informational consistency

Corollary (Observational consistency)

Let X and Y be two processes (on Ω , with time domain $T \in \{\mathbb{N}_0, [0, \infty)\}$ and values in (E, \mathcal{E})), S an \mathcal{F}^X and an \mathcal{F}^Y -stopping time. Suppose furthermore $X^S = Y^S$. If any one of the conditions (1) $T = \mathbb{N}_0$.

- (2) $\operatorname{Im} X = \operatorname{Im} Y$.
- (3) (a) (Ω, G) (resp. (Ω, H)) is Blackwell for some σ-field G ⊃ F_∞^X (resp. H ⊃ F_∞^Y).
 (b) σ(X^S) (resp. σ(Y^S)) is separable and contained in F_S^X (resp. F_S^Y).
 (c) (ImX^S, E^{⊗T}|_{ImX^S}) (resp. (ImY^S, E^{⊗T}|_{ImY^S})) is Hausdorff.

is met, then $\mathcal{F}_S^X = \mathcal{F}_S^Y$.

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The measure-theoretic case

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Key results - monotonicity of information

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Key results - monotonicity of information

Proposition (Monotonicity of information)

Let Z be a process (on Ω , with time domain $T \in \{\mathbb{N}_0, [0, \infty)\}$ and values in (E, \mathcal{E})), $U \leq V$ two stopping times of \mathcal{F}^Z . If either $T = \mathbb{N}_0$ or else the conditions:

• (Ω, \mathcal{G}) is Blackwell for some σ -field $\mathcal{G} \supset \sigma(Z^V) \lor \sigma(Z^U)$.

$$(Im Z^V, \mathcal{E}^{\otimes T}|_{Im Z^V}) \text{ is Hausdorff.}$$

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$$\sigma(Z^V)$$
 is separable.

are met, then $\sigma(Z^U) \subset \sigma(Z^V)$.

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Case with completions...

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Case with completions...

... is much more involved.

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 Unclear how to extend *directly* the 'measure-theoretic' approach (for one, completions of 'nice' spaces, aren't /the same kind of/ 'nice').

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- Are true, if the stopping times are predictable

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A counter-example

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A counter-example

Example

Let $\Omega = (0, \infty) \times \{-2, -1, 0\}$ be endowed with the law $P = Exp(1) \times Unif(\{-2, -1, 0\})$, defined on the tensor product of the Lebesgue σ -field on $(0,\infty)$ and the power set of $\{-2,-1,0\}$. Denote by e, respectively I, the projection onto the first, respectively second, coordinate. Define the process $X_t := I(t-e)\mathbb{1}_{[0,t]}(e)$, $t \in [0,\infty)$, and the process $Y_t := (-1)(t-e)\mathbb{1}_{[0,t]}(e)\mathbb{1}_{\{-1,-2\}} \circ I, t \in [0,\infty)$. The completed natural filtrations of X and Y are already right-continuous. The first entrance time S of X into $(-\infty, 0)$ is equal to the first entrance time of Y into $(-\infty, 0)$, and this is a stopping time of $\overline{\mathcal{F}^X}^P$ as it is of $\overline{\mathcal{F}^Y}^{\mathsf{P}}$ (but not of \mathcal{F}^X and not of \mathcal{F}^Y). Moreover, $X^S = 0 = Y^S$. Finally, consider the event $A := \{I = -1\}$. Then $A \in \overline{\mathcal{F}^X}^{\mathsf{P}}_{\mathsf{S}}$, however, $A \notin \overline{\mathcal{F}^Y}^{\mathsf{P}}_{\mathsf{S}}.$ \diamond

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Handling the predictable case (in continuous time)

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Handling the predictable case (in continuous time)

Proposition

Let $T = [0, \infty)$, \mathcal{G} be a filtration on Ω . Let furthermore P be a complete probability measure on Ω , whose domain includes \mathcal{G}_{∞} ; S a predictable stopping time relative to $\overline{\mathcal{G}}^{\mathsf{P}}$. Then S is P-a.s. equal to a predictable stopping time P of \mathcal{G} . Moreover, if U is any \mathcal{G} -stopping time, P-a.s. equal to S, then $\overline{\mathcal{G}}_{S}^{\mathsf{P}} = \overline{\mathcal{G}_{U}}^{\mathsf{P}}$. Finally, if S' is another random time, P-a.s equal to S, then it is a $\overline{\mathcal{G}}^{\mathsf{P}}$ -stopping time, and $\overline{\mathcal{G}}_{S}^{\mathsf{P}} = \overline{\mathcal{G}}_{S'}^{\mathsf{P}}$.

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Further work?

On the informational structure in optimal dynamic stochastic control {arXiv:1503.02375}

Matija Vidmar

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Further work?

 Regarding the 'technical' condition: A more precise investigation into the relationship between the validity of Bellman's principle, and the linking between C, G and the collection (*G*^c)_{c∈C}.

Further work?

- Regarding the 'technical' condition: A more precise investigation into the relationship between the validity of Bellman's principle, and the linking between C, G and the collection (*G*^c)_{c∈C}.
- Regarding the theme of informational consistency: Try and relax/drop the Blackwell-ian assumption. Alternatively (or in addition) find relevant counter-examples!

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