Introduction MKV-MDP Application

# Markov decision process under mean-field interaction and application to targeted advertising

#### Médéric MOTTE

Université de Paris, LPSM

Based on joint work with Huyên PHAM, Université de Paris, LPSM

European summer school in financial mathematics Padova, Sept 2-6, 2019

• Large number of N interacting dynamic agents

- Large number of N interacting dynamic agents
- Center of decision on top of the population

- Large number of N interacting dynamic agents
- Center of decision on top of the population
  - Social planner aims to optimize the global gain/cost of collectivity
     → Pareto efficiency ≠ Nash equilibrium

- Large number of N interacting dynamic agents
- Center of decision on top of the population
  - Social planner aims to optimize the global gain/cost of collectivity  $\rightarrow$  Pareto efficiency  $\neq$  Nash equilibrium
  - **Influencer** control the state of all players, e.g. through advertising in models of herd behavior/connected people

- Large number of N interacting dynamic agents
- Center of decision on top of the population
  - Social planner aims to optimize the global gain/cost of collectivity  $\rightarrow$  Pareto efficiency  $\neq$  Nash equilibrium
  - **Influencer** control the state of all players, e.g. through advertising in models of herd behavior/connected people
- ► Our main focus:

- Large number of N interacting dynamic agents
- Center of decision on top of the population
  - Social planner aims to optimize the global gain/cost of collectivity  $\rightarrow$  Pareto efficiency  $\neq$  Nash equilibrium
  - **Influencer** control the state of all players, e.g. through advertising in models of herd behavior/connected people
- ► Our main focus:
  - Discrete time and space

- Large number of N interacting dynamic agents
- Center of decision on top of the population
  - Social planner aims to optimize the global gain/cost of collectivity  $\rightarrow$  Pareto efficiency  $\neq$  Nash equilibrium
  - **Influencer** control the state of all players, e.g. through advertising in models of herd behavior/connected people
- ► Our main focus:
  - Discrete time and space
  - When  $N \rightarrow \infty$ : McKean-Vlasov Markov Decision Process (MKV-MDP)

\_ ∢ ⊒ →

Introduction MKV-MDP Application

#### A motivating targeted advertising example

• A (phone) company C (the influencer),

→ < ∃→

- A (phone) company C (the influencer),
- A social network SN

→ < ∃→

- A (phone) company C (the influencer),
- A social network SN
  - N connected users of SN: state = client or not of C

∢ ≣ ▶

- A (phone) company C (the influencer),
- A social network SN
  - *N* connected users of SN: state = client or not of *C*
  - Users data: cookies

∢ ≣ ▶

- A (phone) company C (the influencer),
- A social network SN
  - *N* connected users of SN: state = client or not of *C*
  - Users data: cookies

► **Targeted advertising**: SN can display ads for *C* to some users according to their cookies.

• For each user *i*, cookies:

< ∃⇒

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$

< ∃⇒

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$
  - At any time t, additional information  $\varepsilon_t^i,$  e.g. time spent on a forum discussing about phones

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$
  - At any time t, additional information  $\varepsilon_t^i$ , e.g. time spent on a forum discussing about phones
- A program is implemented on each laptop based on the cookies for displaying ads. This program is the same on each laptop

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$
  - At any time t, additional information  $\varepsilon_t^i,$  e.g. time spent on a forum discussing about phones
- A program is implemented on each laptop based on the cookies for displaying ads. This program is the same on each laptop
- $\rightarrow$  Same policy:  $\alpha_t^i = \pi_t(\Gamma^i, \varepsilon_1^i, \ldots, \varepsilon_t^i)$

-∢ ≣ ▶

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$
  - At any time t, additional information  $\varepsilon_t^i,$  e.g. time spent on a forum discussing about phones

• A program is implemented on each laptop based on the cookies for displaying ads. This program is the same on each laptop  $\rightarrow$  Same policy:  $\alpha_t^i = \pi_t(\Gamma^i, \varepsilon_1^i, \dots, \varepsilon_t^i)$ 

**Remark:** The program does not have access to the states of the individuals, but to the cookies:  $\rightarrow$  "Open-loop" policy.

\_ ∢ ⊒ →

- For each user *i*, cookies:
  - Initial information  $\Gamma^i$
  - At any time t, additional information  $\varepsilon_t^i,$  e.g. time spent on a forum discussing about phones

• A program is implemented on each laptop based on the cookies for displaying ads. This program is the same on each laptop  $\rightarrow$  Same policy:  $\alpha_t^i = \pi_t(\Gamma^i, \varepsilon_1^i, \dots, \varepsilon_t^i)$ 

**Remark:** The program does not have access to the states of the individuals, but to the cookies:  $\rightarrow$  "Open-loop" policy.

► Goal of the company: find the best ad-policy to be displayed by SN in order to attract the largest possible clients given ads costs.

E > < E > 

From N-agents model to MKV-MDP Studying V

#### Framework and notations

• A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$ 

< ∃⇒

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  ${\cal X}$  and A

< ∃⇒

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$

< ∃ →

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics

< ∃ >

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon^0_t)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$

-∢ ≣ ▶

• A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$ 

• State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$ 

- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon_t^0)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$
  - F: meas. function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A) \times W \times W^0$  into  $\mathcal{X}$

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon^0_t)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$
  - F: meas. function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A) \times W \times W^0$  into  $\mathcal{X}$
- Reward on infinite horizon:

∃ ► < ∃ ►</p>

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon_t^0)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$
  - F: meas. function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A) \times W \times W^0$  into  $\mathcal{X}$
- Reward on infinite horizon:
  - discount factor  $\beta \in [0, 1)$

医下 不至下

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon_t^0)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$
  - F: meas. function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A) \times W \times W^0$  into  $\mathcal{X}$
- Reward on infinite horizon:
  - discount factor  $\beta \in [0, 1)$
  - f: measurable function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A)$  into  $\mathbb{R}$

< 国 > (4 国 > ))

- A universal probability space  $(\Omega, \mathcal{F}, \mathbb{P})$
- State and control/action (compact Polish) spaces:  $\mathcal{X}$  and  $\mathcal{A}$   $\mathcal{P}(\mathcal{X})$ , resp.  $\mathcal{P}(\mathcal{A})$ : set of probability measures on  $\mathcal{X}$ , resp.  $\mathcal{A}$
- (Discrete time) transition dynamics
  - Idiosyncratic noises:  $(\varepsilon_t^i)_{t\in\mathbb{N}}$ , for agent  $i\in\mathbb{N}^*$ , i.i.d. valued in W
  - Common noise:  $(\varepsilon^0_t)_{t\in\mathbb{N}}$  for all agents, i.i.d. valued in  $W^0$
  - F: meas. function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A) \times W \times W^0$  into  $\mathcal{X}$
- Reward on infinite horizon:
  - discount factor  $\beta \in [0, 1)$
  - f: measurable function from  $\mathcal{X} \times A \times \mathcal{P}(\mathcal{X}) \times \mathcal{P}(A)$  into  $\mathbb{R}$

**Remark**: F and f do not depend on i: indistinguishable agents

#### • Information:

•  $\Gamma^i$ ,  $i \in \mathbb{N}^*$ , i.i.d. valued in *I*: initial information (agent *i*)

≣ ► < ≣ ►

#### • Information:

- $\Gamma^i$ ,  $i \in \mathbb{N}^*$ , i.i.d. valued in *I*: initial information (agent *i*)
- Initial state =  $\xi(\Gamma^i)$

∃ ► < ∃ ►</p>

#### • Information:

- $\Gamma^i$ ,  $i \in \mathbb{N}^*$ , i.i.d. valued in *I*: initial information (agent *i*)
- Initial state =  $\xi(\Gamma^i)$

• **Open-loop Policy**: measurable sequence  $\pi \in \prod_{OL}^{r}$  of functions  $\pi_t$ ,  $t \in \mathbb{N}$ , from  $I \times W^t \times (W^0)^t$  into A

글 🕨 🖌 글 🕨

#### • Information:

- $\Gamma^i$ ,  $i \in \mathbb{N}^*$ , i.i.d. valued in *I*: initial information (agent *i*)
- Initial state =  $\xi(\Gamma^i)$

• **Open-loop Policy**: measurable sequence  $\pi \in \prod_{OL}^r$  of functions  $\pi_t$ ,  $t \in \mathbb{N}$ , from  $I \times W^t \times (W^0)^t$  into  $A \leftrightarrow$  Open-loop (nonanticipative) control for agent *i*:

$$\alpha_t^{\pi,i} = \pi_t(\Gamma^i, \varepsilon_1^i, \dots, \varepsilon_t^i, \varepsilon_1^0, \dots, \varepsilon_t^0),$$

医下子 医下

#### • Information:

- $\Gamma^i$ ,  $i \in \mathbb{N}^*$ , i.i.d. valued in *I*: initial information (agent *i*)
- Initial state =  $\xi(\Gamma^i)$

• **Open-loop Policy**: measurable sequence  $\pi \in \prod_{OL}^{r}$  of functions  $\pi_t$ ,  $t \in \mathbb{N}$ , from  $I \times W^t \times (W^0)^t$  into  $A \leftrightarrow$  Open-loop (nonanticipative) control for agent *i*:

$$\alpha_t^{\pi,i} = \pi_t(\Gamma^i, \varepsilon_1^i, \ldots, \varepsilon_t^i, \varepsilon_1^0, \ldots, \varepsilon_t^0),$$

**Remark**: each agent has only access to her own initial information, idiosyncratic and common noise, but follows the same policy.

◆ 臣 ▶ | ◆ 臣 ▶ | |
- Mean-field controlled dynamics:
  - Same initial state function  $\xi \in L(I; \mathcal{X})$ , and same open-loop policy  $\pi$

< ∃ →

- Mean-field controlled dynamics:
  - Same initial state function  $\xi \in L(I; \mathcal{X})$ , and same open-loop policy  $\pi$
  - State process X<sup>*i*,N</sup> of agent *i*

-∢ ≣ ▶

- Mean-field controlled dynamics:
  - Same initial state function  $\xi \in L(I; \mathcal{X})$ , and same open-loop policy  $\pi$
  - State process X<sup>*i*,N</sup> of agent *i*

$$\left\{ \begin{array}{ll} X_{0}^{i,N} & = & \xi(\Gamma^{i}) \\ X_{t+1}^{i,N} & = & F(X_{t}^{i,N},\alpha_{t}^{\pi,i},\frac{1}{N}\sum_{j=1}^{N}\delta_{\chi_{t}^{j,N}},\frac{1}{N}\sum_{j=1}^{N}\delta_{\alpha_{t}^{\pi,j}},\varepsilon_{t+1}^{i}). \end{array} \right.$$

-∢ ≣ ▶

- Mean-field controlled dynamics:
  - Same initial state function  $\xi \in L(I; \mathcal{X})$ , and same open-loop policy  $\pi$
  - State process X<sup>*i*,N</sup> of agent *i*

$$\left\{ \begin{array}{lll} X_{0}^{i,N} & = & \xi(\Gamma^i) \\ X_{t+1}^{i,N} & = & F(X_t^{i,N},\alpha_t^{\pi,i},\frac{1}{N}\sum_{j=1}^N\delta_{x_t^{j,N}},\frac{1}{N}\sum_{j=1}^N\delta_{\alpha_t^{\pi,j}},\varepsilon_{t+1}^i). \end{array} \right.$$

• Gain functional identical for each agent *i* by indistinguishability:

$$V_N^{\pi}(\xi) = \mathbb{E}\Big[\sum_{t=0}^{\infty} \beta^t f\big(X_t^{i,N}, \alpha_t^{\pi,i}, \frac{1}{N} \sum_{j=1}^N \delta_{x_t^{j,N}}, \frac{1}{N} \sum_{j=1}^N \delta_{\alpha_t^{\pi,j}}\big)\Big]$$

ヨト・モト

- Mean-field controlled dynamics:
  - Same initial state function  $\xi \in L(I; \mathcal{X})$ , and same open-loop policy  $\pi$
  - State process X<sup>i,N</sup> of agent i

$$\left\{ \begin{array}{lll} X_{0}^{i,N} & = & \xi(\Gamma^i) \\ X_{t+1}^{i,N} & = & F(X_t^{i,N},\alpha_t^{\pi,i},\frac{1}{N}\sum_{j=1}^N\delta_{x_t^{j,N}},\frac{1}{N}\sum_{j=1}^N\delta_{\alpha_t^{\pi,j}},\varepsilon_{t+1}^i). \end{array} \right.$$

• Gain functional identical for each agent *i* by indistinguishability:

$$V_N^{\pi}(\xi) = \mathbb{E}\Big[\sum_{t=0}^{\infty} \beta^t f\big(X_t^{i,N}, \alpha_t^{\pi,i}, \frac{1}{N}\sum_{j=1}^N \delta_{X_t^{j,N}}, \frac{1}{N}\sum_{j=1}^N \delta_{\alpha_t^{\pi,j}}\big)\Big]$$

▶ Optimal gain for the center of decision (social planner/influencer):

$$V_N(\xi) = \sup_{\pi \in \Pi_{OL}^r} V_N^{\pi}(\xi).$$

토 🖌 🛪 토 🛌

From N-agents model to MKV-MDP Studying V

# Limiting problem ( $N \rightarrow \infty$ ): MKV-MDP

- Mean-field controlled dynamics:
  - Initial state function  $\xi \in L(I; \mathcal{X})$ , and open-loop policy  $\pi$

< 臣 > < 臣 > □

From *N*-agents model to MKV-MDP Studying V

# Limiting problem ( $N \rightarrow \infty$ ): MKV-MDP

- Mean-field controlled dynamics:
  - Initial state function  $\xi \in L(I; \mathcal{X})$ , and open-loop policy  $\pi$
  - State process  $X^i$  of agent *i* in the infinite population

$$\begin{cases} X_0^i &= \xi(\Gamma^i) \\ X_{t+1}^i &= F(X_t^i, \alpha_t^{\pi,i}, \mathbb{P}^0_{X_t^i}, \mathbb{P}^0_{\alpha_t^{\pi,i}}, \varepsilon_{t+1}^i). \end{cases}$$

< 国 > ( 国 > )

From *N*-agents model to MKV-MDP Studying V

# Limiting problem ( $N \rightarrow \infty$ ): MKV-MDP

- Mean-field controlled dynamics:
  - Initial state function  $\xi \in L(I; \mathcal{X})$ , and open-loop policy  $\pi$
  - State process  $X^i$  of agent *i* in the infinite population

$$\begin{cases} X_0^i &= \xi(\Gamma^i) \\ X_{t+1}^i &= F(X_t^i, \alpha_t^{\pi,i}, \mathbb{P}^0_{X_t^i}, \mathbb{P}^0_{\alpha_t^{\pi,i}}, \varepsilon_{t+1}^i). \end{cases}$$

• Gain functional identical for each agent i by indistinguishability:

$$V^{\pi}(\xi) = \mathbb{E}\Big[\sum_{t=0}^{\infty} \beta^{t} f(X_{t}^{i}, \alpha_{t}^{\pi, i}, \mathbb{P}_{X_{t}^{i}}^{0}, \mathbb{P}_{\alpha_{t}^{\pi, i}}^{0})\Big]$$

< 注 → < 注 → □ Ξ

From *N*-agents model to MKV-MDP Studying V

# Limiting problem ( $N \rightarrow \infty$ ): MKV-MDP

- Mean-field controlled dynamics:
  - Initial state function  $\xi \in L(I; \mathcal{X})$ , and open-loop policy  $\pi$
  - State process  $X^i$  of agent *i* in the infinite population

$$\begin{cases} X_0^i &= \xi(\Gamma^i) \\ X_{t+1}^i &= F(X_t^i, \alpha_t^{\pi,i}, \mathbb{P}^{\mathbf{0}}_{X_t^i}, \mathbb{P}^{\mathbf{0}}_{\alpha_t^{\pi,i}}, \varepsilon_{t+1}^i). \end{cases}$$

• Gain functional identical for each agent i by indistinguishability:

$$V^{\pi}(\xi) = \mathbb{E}\Big[\sum_{t=0}^{\infty} \beta^{t} f\big(X_{t}^{i}, \alpha_{t}^{\pi, i}, \mathbb{P}_{X_{t}^{i}}^{0}, \mathbb{P}_{\alpha_{t}^{\pi, i}}^{0}\big)\Big]$$

▶ Optimal gain for the center of decision (social planner/influencer):

$$V(\xi) = \sup_{\pi \in \Pi'_{OL}} V^{\pi}(\xi).$$

From *N*-agents model to MKV-MDP Studying *V* 

## Convergence of the N-agents model

• Propagation of chaos: convergence of the mean-field dynamics

< ∃⇒

From *N*-agents model to MKV-MDP Studying *V* 

## Convergence of the N-agents model

• Propagation of chaos: convergence of the mean-field dynamics

#### Proposition

Under suitable continuity assumptions on F, given  $\xi$  and  $\pi$ , we have for all  $i \in \mathbb{N}$ ,  $t \in \mathbb{N}$ ,

$$X^{i,N}_t \xrightarrow[N \to \infty]{a.s.} X^i_t, \quad d_W \left( \frac{1}{N} \sum_{j=1}^N \delta_{X^{j,N}_t}, \mathbb{P}^0_{X^i_t} \right) \xrightarrow[N \to \infty]{a.s.} 0.$$

4 E b

From *N*-agents model to MKV-MDP Studying *V* 

## Convergence of the *N*-agents model

• Propagation of chaos: convergence of the mean-field dynamics

#### Proposition

Under suitable continuity assumptions on F, given  $\xi$  and  $\pi$ , we have for all  $i \in \mathbb{N}$ ,  $t \in \mathbb{N}$ ,

$$X^{i,N}_t \xrightarrow[N \to \infty]{a.s.} X^i_t, \quad d_W \left( \frac{1}{N} \sum_{j=1}^N \delta_{X^{j,N}_t}, \mathbb{P}^0_{X^i_t} \right) \xrightarrow[N \to \infty]{a.s.} 0.$$

• Convergence towards MKV-MDP

< ∃ →

# Convergence of the N-agents model

• Propagation of chaos: convergence of the mean-field dynamics

#### Proposition

Under suitable continuity assumptions on F, given  $\xi$  and  $\pi$ , we have for all  $i \in \mathbb{N}$ ,  $t \in \mathbb{N}$ ,

$$X_t^{i,N} \xrightarrow[N \to \infty]{a.s.} X_t^i, \quad d_W \left( \frac{1}{N} \sum_{j=1}^N \delta_{X_t^{j,N}}, \mathbb{P}^0_{X_t^j} \right) \xrightarrow[N \to \infty]{a.s.} 0.$$

• Convergence towards MKV-MDP

#### Theorem

Under Lipschitz condition on f, we have for all initial state function  $\xi$ :

$$\sup_{\pi\in\Pi_{OL}}|V_N^{\pi}(\xi)-V^{\pi}(\xi)|\underset{N\to\infty}{\longrightarrow}0.$$

Consequently,  $V_N \xrightarrow[N \to \infty]{} V$  and any  $\varepsilon$ -optimal strategy for the limit model is an  $\varepsilon$ -optimal strategy for the *N*-individual model for *N* large enough

From N-agents model to MKV-MDP Studying V

# Studying V

#### Proposition

*F* Lipschitz  $\Rightarrow$  *V*<sup> $\pi$ </sup> uniformly continuous, uniformly on  $\pi$   $\Rightarrow$  *V* unif. cont.

・ロト ・四ト ・ヨト ・ヨトー

æ

From N-agents model to MKV-MDP Studying V

# Studying V

#### Proposition

F Lipschitz  $\Rightarrow$  V<sup> $\pi$ </sup> uniformly continuous, uniformly on  $\pi$   $\Rightarrow$  V unif. cont.

**Hyp. A (randomization)**: Exists i.i.d. uniform  $(U_t(\Gamma))_{t\in\mathbb{N}}$  indep of  $\xi(\Gamma)$ . (equivalent : only one)

< 4 Im ▶

From N-agents model to MKV-MDP Studying V

# Studying V

#### Proposition

F Lipschitz  $\Rightarrow$  V<sup> $\pi$ </sup> uniformly continuous, uniformly on  $\pi$   $\Rightarrow$  V unif. cont.

**Hyp. A (randomization)**: Exists i.i.d. uniform  $(U_t(\Gamma))_{t\in\mathbb{N}}$  indep of  $\xi(\Gamma)$ . (equivalent : only one)

#### Proposition (Law-invariance)

For any  $\xi, \, \widetilde{\xi} \in L(I; \mathcal{X})$  satisfying **A**, s.t.  $\mathbb{P}_{\xi} = \mathbb{P}_{\widetilde{\xi}}$ , we have

$$V(\xi) = V(\widetilde{\xi}).$$

From N-agents model to MKV-MDP Studying V

### Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$V(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{0}_{X_{1}^{\xi, a}}) \Big]$$

・ロン ・聞と ・ 聞と ・ 聞と

From N-agents model to MKV-MDP Studying V

## Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$V(\mu) = \sup_{\mathbf{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \mathbf{a}(\xi, U), \mu, \mathbb{P}_{\mathbf{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{0}_{X_{1}^{\xi, \mathfrak{a}}}) \Big]$$

Useful to study V:

< 臣 > < 臣 > □

< 4 ► >

From N-agents model to MKV-MDP Studying V

## Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$V(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{0}_{X_{1}^{\xi,a}}) \Big]$$

Useful to study V:

- Convexity?
- Lipschitz?

< 臣 > < 臣 > □

From N-agents model to MKV-MDP Studying V

## Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$\mathcal{V}(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1]; A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{0}_{X_{1}^{\xi, a}}) \Big]$$

Useful to study V:

- Convexity?
- Lipschitz?

max reached measurably in  $\mu \Rightarrow$  stationary feedback policy. Issues:

From *N*-agents model to MKV-MDP Studying *V* 

## Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$\mathcal{V}(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{\boldsymbol{0}}_{\boldsymbol{X}_{1}^{\xi, \boldsymbol{a}}}) \Big]$$

Useful to study V:

- Convexity?
- Lipschitz?

max reached measurably in  $\mu \Rightarrow$  stationary feedback policy. Issues:

• sup on an  $\infty$ -dimensional space + iterations.

From N-agents model to MKV-MDP Studying V

## Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$\mathcal{V}(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{\boldsymbol{0}}_{\boldsymbol{X}_{1}^{\xi, \boldsymbol{a}}}) \Big]$$

Useful to study V:

- Convexity?
- Lipschitz?

max reached measurably in  $\mu \Rightarrow$  stationary feedback policy. Issues:

- sup on an  $\infty$ -dimensional space + iterations.
- Hard to store policies.

From *N*-agents model to MKV-MDP Studying *V* 

### Theorem (Dynamic Programming Principle)

For any  $\mu \in \mathcal{P}(\mathcal{X})$ ,

$$\mathcal{V}(\mu) = \sup_{\boldsymbol{a} \in L(\mathcal{X} \times [0,1];A)} \mathbb{E} \Big[ f\big(\xi, \boldsymbol{a}(\xi, U), \mu, \mathbb{P}_{\boldsymbol{a}(\xi, U)}\big) + \beta V(\mathbb{P}^{\boldsymbol{0}}_{\boldsymbol{X}_{1}^{\xi, \boldsymbol{a}}}) \Big]$$

Useful to study V:

- Convexity?
- Lipschitz?

max reached measurably in  $\mu \Rightarrow$  stationary feedback policy. Issues:

- sup on an  $\infty$ -dimensional space + iterations.
- Hard to store policies.
- Hard to compute X.

From N-agents model to MKV-MDP Studying V

### Proposition

 $\mathcal{X}$ ,  $\mathcal{A}$  finite  $\Rightarrow$  equivalent to MDP on state/action spaces  $[0,1]^n$ .

★ 문 ► ★ 문 ►

From N-agents model to MKV-MDP Studying V

### Proposition

 $\mathcal{X}$ ,  $\mathcal{A}$  finite  $\Rightarrow$  equivalent to MDP on state/action spaces  $[0,1]^n$ .

$$\begin{array}{rcl} X_t & \to & (\mathbb{P}(X_t = x))_{x \in \mathcal{X}} \\ \alpha_t & \to & (\mathbb{P}(\alpha_t = a \mid X_t = x))_{a \in A, x \in \mathcal{X}} \end{array}$$

< (F) >

- < 注 → - < 注 → -

From N-agents model to MKV-MDP Studying V

#### Proposition

 $\mathcal{X}$ ,  $\mathcal{A}$  finite  $\Rightarrow$  equivalent to MDP on state/action spaces  $[0,1]^n$ .

$$\begin{array}{rcl} X_t & \to & (\mathbb{P}(X_t = x))_{x \in \mathcal{X}} \\ \alpha_t & \to & (\mathbb{P}(\alpha_t = a \mid X_t = x))_{a \in \mathcal{A}, x \in \mathcal{X}} \end{array}$$

- Dynamic inherits Lipschitz property from  $F \rightarrow MDP$  algo applies.
- $(\mathbb{P}_{X_t^{\vartheta}})_t = \text{simple vectors in } [0,1]^{|\mathcal{X}|-1}.$
- Easy to compute perfectly
- $\mathcal{X}$ ,  $\mathcal{A}$  not finite  $\rightarrow$  discretization  $\rightarrow$  finite spaces.

Back to targeted advertising example: spaces and noise

- State space  $\mathcal{X} = \{0, 1\}$ :
  - x = 1 (resp. 0): customer (not customer) of the company C

## Back to targeted advertising example: spaces and noise

- State space  $\mathcal{X} = \{0, 1\}$ :
  - x = 1 (resp. 0): customer (not customer) of the company C
- Action space  $A = \{0, 1\}$ :
  - a = 1 (resp. 0): SN send (or not) an ad

글 🕨 🖌 글 🕨

## Back to targeted advertising example: spaces and noise

- State space  $\mathcal{X} = \{0, 1\}$ :
  - x = 1 (resp. 0): customer (not customer) of the company C
- Action space  $A = \{0, 1\}$ :
  - a = 1 (resp. 0): SN send (or not) an ad
- For each player *i*:
  - $\varepsilon_t^i$ : uniform r.v. representing e.g. time spent at day t on a forum about phones
- For simplicity, no common noise

医下颌 医下颌

Introduction Application

Targeted advertising example: dynamics and reward

• State transition function:

$$F(x, \mu, a, e) = \begin{cases} \mathbf{1}_{e > \mu(\{0\}) - \eta a} & \text{if } x = 0\\ \mathbf{1}_{e < \mu(\{1\}) + \eta a} & \text{if } x = 1. \end{cases}$$

≣ ► < ≣ ►

Introduction Application

## Targeted advertising example: dynamics and reward

• State transition function:

$$F(x, \mu, a, e) = \begin{cases} \mathbf{1}_{e > \mu(\{0\}) - \eta a} & \text{if } x = 0\\ \mathbf{1}_{e < \mu(\{1\}) + \eta a} & \text{if } x = 1. \end{cases}$$

• Large e: eager to change of phone

∃ ► < ∃ ►</p>

Targeted advertising example: dynamics and reward

• State transition function:

$$F(x, \mu, a, e) = \begin{cases} \mathbf{1}_{e > \mu(\{0\}) - \eta a} & \text{if } x = 0\\ \mathbf{1}_{e < \mu(\{1\}) + \eta a} & \text{if } x = 1. \end{cases}$$

- Large e: eager to change of phone
- $\mu(\{0\})$ : proportion of *SN* users that are not customers of *C*

∃ ► < ∃ ►</p>

## Targeted advertising example: dynamics and reward

• State transition function:

$$F(x, \mu, a, e) = \begin{cases} \mathbf{1}_{e > \mu(\{0\}) - \eta a} & \text{if } x = 0\\ \mathbf{1}_{e < \mu(\{1\}) + \eta a} & \text{if } x = 1. \end{cases}$$

- Large e: eager to change of phone
- $\mu(\{0\})$ : proportion of *SN* users that are not customers of *C*
- $\eta > 0$ : impact of ad for incentive to become or remain a customer of C

글 🕨 🖌 글 🕨

## Targeted advertising example: dynamics and reward

• State transition function:

$$F(x, \mu, a, e) = \begin{cases} \mathbf{1}_{e > \mu(\{0\}) - \eta a} & \text{if } x = 0\\ \mathbf{1}_{e < \mu(\{1\}) + \eta a} & \text{if } x = 1. \end{cases}$$

- Large e: eager to change of phone
- $\mu(\{0\})$ : proportion of *SN* users that are not customers of *C*
- $\eta > 0$ : impact of ad for incentive to become or remain a customer of C
- Reward function: for  $x \in \mathcal{X} = \{0, 1\}, a \in A = \{0, 1\},$

$$f(x,a) = x - ca,$$

• c > 0: ad cost

프 🖌 🔺 프 🛌

# Reformulation as MDP on [0, 1]

- $\mathcal{P}(\mathcal{X}) \leftrightarrow$  Bernoulli parameter  $p \in [0,1]$
- $\mathcal{P}(A) \leftrightarrow$  Bernoulli parameter  $q \in [0,1]$
- Policy  $\pi \to p_t^{\pi}$ : Bernoulli parameter of  $\mathbb{P}_{X_t}$ , i.e.  $p_t^{\pi} = \mathbb{E}[X_t]$ :

$$p_{t+1}^{\pi} = \Phi(p_t^{\pi}, q_t^{\pi}) := p_t^{\pi} + q_t^{\pi} \min(\eta, 1 - p_t^{\pi}), \ t \in \mathbb{N},$$

where

- $q_t^{\pi} = \mathbb{E}[\alpha_t^{\pi}]$ : probability of displaying an ad  $\equiv$  sending an ad to  $q_t^{\pi}$  proportion of the SN users
- ► Value function on [0, 1]:

$$V(p) = \sup_{q_t^{\pi} \in [0,1]} \sum_{t=0}^{\infty} \beta^t (p_t^{\pi} - cq_t^{\pi}), \quad p \in [0,1],$$

satisfying the DP:

$$V(p) = \sup_{q \in [0,1]} \left[ p - cq + \beta V \left( p + \min(\eta, 1-p) \right) \right]$$

Analytical resolution

# Variational graph



Maximal variations F(p, 1) - p (in blue).

医▶ ★ 医▶ -

æ
Analytical resolution

## Disjunction



Disjunction according to the position of  $\frac{c}{\eta}$  relative to  $\beta$  and  $\frac{\beta}{1-\beta}$ .

医下 不臣下

Analytical resolution



Analytical resolution



Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

< 臣 → < 臣 → …

æ

Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

\* 医 \* \* 医 \* … 臣

Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

\* 医 \* \* 医 \* … 臣

Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

< A ►

Analytical resolution

## **Optimal** variation



Case  $\frac{c}{n} < \beta$ . Variational optimal policy (in red).

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

< 注 → < 注 → .

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

< 注 → < 注 → .

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

< 注 > < 注 >

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

< 注 > < 注 >

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

注入 不注入

Analytical resolution

#### **Optimal** variation



Case  $\frac{c}{\eta} < \beta$ . Variational optimal policy, Bang-Bang.

臣▶ ★ 臣▶

Analytical resolution

# Optimal policy



Analytical resolution

## Optimal value



Case  $\frac{c}{n} < \beta$ . Optimal value (in red) against "no ad" value (in blue).

- ∢ ≣ ▶

Analytical resolution



Analytical resolution



Analytical resolution



Analytical resolution



Analytical resolution



Analytical resolution



Analytical resolution

## **Optimal** variation



Analytical resolution

## **Optimal** variation



Analytical resolution

## **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy (in red).

Analytical resolution

## **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy (in red).

Analytical resolution

## **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy (in red).

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

æ

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

< 臣 > < 臣 > □

э

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

< 臣 > < 臣 > □

э

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

< 臣 > < 臣 > □

э

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

Analytical resolution

#### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.
Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, "jump to  $1 - \eta$ " case.

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

< 17 ▶

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

▲ 문 ▶ ▲ 문 ▶ …

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

▲ 문 ▶ ▲ 문 ▶ …

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

< 臣 > < 臣 > □

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

Analytical resolution

### **Optimal** variation



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Variational optimal policy, Bang-Bang case.

Analytical resolution

### **Optimal** control



Analytical resolution

# **Optimal policy**



Case  $\beta < \frac{c}{\eta} < \frac{\beta}{1-\beta}$ . Optimal value (in red) against "no ad" value (in blue).

Analytical resolution

### **Optimal** variation



Analytical resolution

## **Optimal** control



Analytical resolution

# Optimal value



Case  $\beta < \frac{c}{n} < \frac{\beta}{1-\beta}$ . Optimal value (in red) against "no ad" value (in blue).

< E ► < E ►

Analytical resolution

### Sketch of the proof

Let  $(p_t)_{t\in\mathbb{N}}$  = state process from optimal control. Group rewards by increments

$$\Rightarrow V(p_0) = \frac{p_0}{1-\beta} + \sum_{t \in \mathbb{N}} \beta^t (p_{t+1} - p_t) \left( \frac{\beta}{1-\beta} - \frac{c}{\min(\eta, 1-p_t)} \right)$$
  
If  $\frac{\beta}{1-\beta} - \frac{c}{\eta} \leq 0$ ,  $V(p_0) \leq \frac{p_0}{1-\beta} = V^0(p_0) \Rightarrow$  no ad.  
If  $\frac{\beta}{1-\beta} - \frac{c}{\eta} > 0$ :  
• If  $p_t \geq 1 - c \frac{1-\beta}{\beta}$ , then  $\frac{\beta}{1-\beta} - \frac{c}{\min(\eta, 1-p_t)} \leq 0 \Rightarrow$  no ad after  $p_t$ .  
• If  $p_t \in [1-\eta, 1-c \frac{1-\beta}{\beta}]$ , then  
 $\sum_{s \geq t} \beta^s (p_{s+1} - p_s) \left( \frac{\beta}{1-\beta} - \frac{c}{\min(\eta, 1-p_s)} \right)$   
 $\leq \beta^t (1-p_t) \left( \frac{\beta}{1-\beta} - \frac{c}{\min(\eta, 1-p_t)} \right)$ 

 $\Rightarrow q_t = 1 \text{ and } q_s = 0 \text{ for } s > t.$ 

토 🖌 🛪 토 🛌

Analytical resolution

### Sketch of the proof

Still in the case  $\frac{\beta}{1-\beta} - \frac{c}{\eta} > 0$ : If  $p_t \leq 1 - \eta$ : assuming  $p_{t+1} \leq 1 - \eta$ , gain between  $p_t$  and  $p_{t+2}$ :

$$p_t - c \frac{p_{t+1} - p_t}{\eta} + \beta \left( p_{t+1} - c \frac{p_{t+2} - p_{t+1}}{\eta} \right)$$

Derivative in  $p_{t+1}$ :  $-\frac{c}{\eta} + \beta(1 + \frac{c}{\eta}) = (1 - \beta)(\frac{\beta}{1 - \beta} - \frac{c}{\eta}) > 0$ .  $\Rightarrow p_{t+1}$  can't be moved to the right (would contradict optimality). Implies

• if 
$$p_t \leq 1 - 2\eta$$
,  $p_{t+1} = p_t + \eta$ .  
• if  $1 - 2\eta < p_t \leq 1 - \eta$ ,  $p_{t+1} \geq 1 - \eta$ 

医下颌 医下颌

Analytical resolution

# Sketch of the proof

Only thing left:  
If 
$$1 - 2\eta < p_t \leq 1 - \eta$$
, where is  $p_{t+1}$  in  $[1 - \eta, p_t + \eta]$ ?  
Notice:  $p_{t+1}$  known  $\Rightarrow$  rest of the trajectory known  $\Rightarrow V(p_{t+1})$  known.  
DPP  $\Rightarrow$  Maximize  $p_t - c\frac{p_{t+1} - p_t}{\eta} + \beta V(p_{t+1})$  over  
 $p_{t+1} \in [1 - \eta, p_t + \eta] \Rightarrow$  Simple.  
 $\Rightarrow$  Disjunction between  $\frac{c}{\eta} > \beta$  and  $\frac{c}{\eta} \leq \beta$ .

E ► < E ►

Issue with previous application: Control happens too late Nowadays: ad displayed between forum reading and choice

< ∃⇒

Issue with previous application: Control happens too late Nowadays: ad displayed between forum reading and choice  $\Rightarrow \alpha_t$  should depend on  $\varepsilon_{t+1}$ 

< ∃ >

Issue with previous application: Control happens too late Nowadays: ad displayed between forum reading and choice  $\Rightarrow \alpha_t$  should depend on  $\varepsilon_{t+1}$ Problem: not adapted!

< ∃ →

Issue with previous application: Control happens too late Nowadays: ad displayed between forum reading and choice  $\Rightarrow \alpha_t$  should depend on  $\varepsilon_{t+1}$ Problem: not adapted! Solution:  $\alpha_t$  valued in  $A^{[0,1]}$ 

< ∃ →

Issue with previous application: Control happens too late Nowadays: ad displayed between forum reading and choice  $\Rightarrow \alpha_t$  should depend on  $\varepsilon_{t+1}$ Problem: not adapted! Solution:  $\alpha_t$  valued in  $A^{[0,1]}$  $\Rightarrow$  Explicit solution: "Bang-Bang" control. •  $c < \frac{\beta}{1-\beta} \rightarrow$  send ad to all "hesitating" individual.

• 
$$c \geqslant \frac{\beta}{1-\beta} \rightarrow \text{send no ad}.$$

∃ ► < ∃ ►</p>

Analytical resolution

# Thank you for your attention!

문▶ ★ 문▶