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**Optimal Decision Rules in Conditional Probabilistic
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Ricerca operativa. — *Optimal Decision Rules in Conditional Probabilistic Programming*⁽¹⁾. Nota^(*) di A. CHARNES⁽²⁾, WILLIAM W. COOPER⁽³⁾, e MICHAEL J. L. KIRBY⁽⁴⁾, presentata dal Socio B. SEGRE.

RIASSUNTO. — Nella presente Nota si sviluppa una teoria unificata della programmazione probabilistica. Questa, nell'adoperare dei vincoli probabilistici condizionali, porge una caratterizzazione delle classi ottimali di regole stocastiche di decisione. In particolare, vien stabilita l'ottimalità delle regole lineari discretizzate di decisione per la minimizzazione del valore assunto da una funzione concava di variabili di decisioni stocastiche.

INTRODUCTION.

In [1, 2, 3, 4, 5] it has been shown how the study of major forms of probabilistic programming can be carried out from the point of view of chance constrained programming. Past results on the optimality of stochastic decision rules, in computation of specific examples, etc., have depended on sophisticated constructs, elaborate analyses, ingenious devices and in severe restrictions not only on admissible classes of stochastic decision rules but also on the functionals to be optimized. [See references 1-15]. In the following we focus on problems with the seemingly more complicated conditional chance constraints and develop an analytical tool which unifies in form the informational bases of different varieties of probabilistic programming and, at the same time, provides a direct characterization of optimal classes of stochastic decision rules. In particular, the optimality of piecewise linear decision rules is established for the general objective, to minimize the expected value of a concave function of the stochastic decision variables. Characterizations are also developed for the optimal stochastic decision rules for the problem of minimizing the expected value of a general convex (differentiable) function of the stochastic variables. In addition, necessary conditions are developed for other general classes of objective functions. Corollaries are general results for problem with (possibly) non-linear functionals and linear programming under uncertainty constraints. In fact, the results are extended to heretofore never considered mixed systems of conditional chance-constraints and linear programming under uncertainty constraints.

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(1) To Dr. Gunter Karl von Noorden whose thought and hand restored the sight of A. Charnes.

(2) Northwestern University and University of Texas.

(3) Carnegie-Mellon University.

(4) Dalhousie University.

ANALYTICAL RESULTS.

The general n -stage chance-constrained problem with linear conditional chance-constraints and constant structural matrix may be represented as

$$(1) \quad \begin{aligned} & \text{Min EH } (\cdots, x_j(b_1, \cdots, b_{j-1}), \cdots) \\ & \text{s.t. } \bar{P} \left(\sum_{j=1}^i A_{ij} x_j(b_1, \cdots, b_{j-1}) \leq b_i \right) \geq \bar{\alpha}_i \quad i = 1, \cdots, m \\ & \quad x_j(b_1, \cdots, b_{j-1}) \geq 0, \quad j = 1, \cdots, n \end{aligned}$$

where $b_i^T \equiv (b_{i1}, \cdots, b_{im})$, \bar{P} denotes probability conditional on b_1, \cdots, b_{i-1} , $\bar{\alpha}_i^T \equiv (\bar{\alpha}_{i1}, \cdots, \bar{\alpha}_{im_i})$ is a vector of functions of b_1, \cdots, b_{i-1} with all $\bar{\alpha}_{ij}$ in $[0, 1]$, the A_{ij} are constant matrices and E is the expectation operator.

As in [4], these chance-constraints may be inverted to give the equivalent linear inequality constraints:

$$(2) \quad \begin{aligned} & \sum_{j=1}^i A_{ij} x_j(b_1, \cdots, b_{j-1}) \leq \bar{F}_i^{-1}(\bar{\alpha}_i) \quad i = 1, \cdots, m \\ & \quad x_j(b_1, \cdots, b_{j-1}) \geq 0 \quad j = 1, \cdots, n \end{aligned}$$

where $\bar{F}_i^{-1}(\bar{\alpha}_i)$ is the vector of marginal fractiles of b_i conditional on b_1, \cdots, b_{i-1} . Further, in equality form (2) becomes:

$$(3) \quad \begin{aligned} & \sum_{j=1}^i A_{ij} x_j(b_1, \cdots, b_{j-1}) + s_i(b_1, \cdots, b_{i-1}) = \bar{F}_i^{-1}(\bar{\alpha}_i) \quad i = 1, \cdots, m \\ & \quad x_j, s_i \geq 0 \quad i = 1, \cdots, m; j = 1, \cdots, n. \end{aligned}$$

The following system renders in a single form both the previous systems and new mixed systems of conditional chance-constraints and linear programming under uncertainty constraints:

$$(4) \quad \begin{aligned} & \min \text{EH } (\lambda^1, \cdots, \lambda^n) \\ & \text{s.t. } \sum_{j=1}^i P_{ij} \lambda^j(b_1, \cdots, b_{j-1}) = g_i(b_1, \cdots, b_{i-1}) \quad i = 1, \cdots, m \\ & \quad \lambda^j(b_1, \cdots, b_{j-1}) \geq 0 \quad j = 1, \cdots, n. \end{aligned}$$

We assume henceforth that this system is consistent for every (b_1, \cdots, b_n) and that the columns of the P_{ii} have the Opposite Sign Property. [See 13 and 16]. In analyzing the system (4) we assume the information pattern to be the following: The λ^i vector is determined after $\lambda^j, g_j, j = 1, \cdots, i-1$ and $g_i(b_1, \cdots, b_{i-1})$ are known but before all other λ_j, g_j and b_i, \cdots, b_m are known. We call vectors λ^i which are determined recursively in this way "informationally feasible" vectors.

LEMMA 1: Let $L^{i\#}$ denote the vector with matrix components each of whose entries is a left inverse of one of the N_i submatrices of P_{ii} which consist of linearly independent columns.

$$\text{Let } \mu^i \equiv \mu^i(b_1, \dots, b_{i-1}) \equiv (\mu_1^i(b_1, \dots, b_{i-1}), \dots, \mu_{N_i}^i(b_1, \dots, b_{i-1})) \geq 0$$

be a conformable vector of scalars with $\mu^{iT} e = 1$, where e is a vector with all entries unity.

$$\text{Let } K^i \equiv \mu^{iT} L^{i\#}.$$

Then the general informationally feasible decision rule for (4) is defined recursively by:

$$(5) \quad \lambda^i = K^i \left(g_i - \sum_{j=1}^{i-1} P_{ij} \lambda^j \right) \quad \text{where } \lambda^i \geq 0, \quad i = 1, \dots, n.$$

LEMMA 2: The set of informationally feasible decision rules for (4) is convex and spanned by the finite number of extreme points which may be represented recursively by

$$(6) \quad \hat{\lambda}^i = E^i \left(g_i - \sum_{j=1}^{i-1} P_{ij} \hat{\lambda}^j \right), \quad \text{where } \hat{\lambda}^i \geq 0, \quad i = 1, \dots, n$$

and E^i denotes a component of $L^{i\#}$.

Thus each extreme point decision rule is defined by a sequence of left-inverses for which the g_i satisfy a system of linear inequalities defined by these left-inverses.

LEMMA 3: There exists a finite disjoint decomposition of the domain of the b_1, \dots, b_n on each set of which only a finite number of extreme point decision rules hold.

THEOREM 1: If $H(\lambda^1, \dots, \lambda^n)$ is concave, then there exists a vector of optimal decision rules for (4) which is piece-wise linear in the g_i . The pieces correspond to extreme point rules, thus the optimal rules involve shifting between a finite number of linear decision rules.

COROLLARY 1: Piece-wise linear decision rules are optimal for problems with (possibly mixed) systems of conditional chance constraints and linear programming under uncertainty constraints.

THEOREM 2: If $H(\lambda^1, \dots, \lambda^n)$ is convex and differentiable, and the convex set of decision rules has an interior point, then a vector of decision rules $(\lambda^1, \dots, \lambda^n)$ is optimal if and only if

$$(7) \quad \sum_{i=1}^n \frac{\partial H}{\partial \lambda_a^i} \frac{\partial \lambda_a^i}{\partial \mu_{\beta}^i} = \sum_{i=1}^n v_{i\alpha} \frac{\partial \lambda_a^i}{\partial \mu_{\beta}^i} \quad \text{for some } v_{i\alpha} \geq 0$$

and $v_{i\alpha} \lambda_a^i = 0$.

THEOREM 3: If H is differentiable and the convex set of decision rules has an interior point, then (7) is necessary for optimality.

CONCLUSIONS.

The above lemmas and theorems provide a new route for the study of probabilistic programming, including chance-constrained programming, linear programming under uncertainty, etc. Extensions of the above results and specializations permitting sharper conclusions will be developed in forthcoming publications. In particular, further developments characterizing the constraint set and the optimal decision rules from both geometric and algebraic viewpoints will be given. Further results involving other constraint sets and information patterns will be presented. In the meantime the above development provides heretofore missing elements for unifying various approaches to probabilistic programming.

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