

論文 / 著書情報
Article / Book Information

Title	An approximation scheme for stochastic controls in continuous time
Author	Yumiharu Nakano
Journal/Book name	Japan Journal of Industrial and Applied Mathematics, , ,
Issue date	2014, 10
Copyright	The original publication is available at www.springerlink.com .
Note	The final publication is available at Springer via http://dx.doi.org/10.1007/s13160-014-0157-1
Note	このファイルは著者（最終）版です。 This file is author (final) version.

An approximation scheme for stochastic controls in continuous time

Yumiharu Nakano

Graduate School of Innovation Management
Tokyo Institute of Technology
2-12-1 W9-117 Ookayama 152-8552, Tokyo, Japan
e-mail: nakano.y.ai@m.titech.ac.jp

October 11, 2014

Abstract

We propose a simple time-discretization scheme for multi-dimensional optimal stochastic control problems in continuous time. It is based on a probabilistic representation for the convolution of the value function by a probability density function. We show the convergence results under mild conditions on coefficients of the problems by Barles–Souganidis viscosity solution method. Resulting numerical methods allow us to use uncontrolled Markov processes to estimate the conditional expectations in the dynamic programming procedure. Moreover, it can be implemented without the interpolation of the value function or the adjustment of the diffusion matrix.

Key words: Stochastic controls, Hamilton-Jacobi-Bellman equations, Viscosity solutions, Kernel density estimation, Monte Carlo methods.

1 Introduction

We consider the optimal stochastic control problems with a finite horizon $T \in (0, \infty)$ having value function

$$(1.1) \quad \begin{aligned} &v(t, x) \\ &= \inf_{\alpha \in \mathcal{A}} \mathbb{E} \left[f(X_T^{t,x,\alpha}) e^{-\int_t^T \ell(s, X_s^{t,x,\alpha}, \alpha_s) ds} + \int_t^T g(s, X_s^{t,x,\alpha}, \alpha_s) e^{-\int_t^s \ell(r, X_r^{t,x,\alpha}, \alpha_r) dr} ds \right] \end{aligned}$$

for $(t, x) \in [0, T] \times \mathbb{R}^m$, where the controlled process $\{X_s^{t,x,\alpha}\}$ is governed by

$$(1.2) \quad \begin{cases} dX_s^{t,x,\alpha} = \mu(s, X_s^{t,x,\alpha}, \alpha_s) ds + \sigma(s, X_s^{t,x,\alpha}, \alpha_s) dW_s, & s \in [t, T], \\ X_t^{t,x,\alpha} = x \in \mathbb{R}^m. \end{cases}$$

Here, $\mu : [0, T] \times \mathbb{R}^m \times A \rightarrow \mathbb{R}^m$, $\sigma : [0, T] \times \mathbb{R}^m \times A \rightarrow \mathbb{R}^{m \times d}$, $f : \mathbb{R}^m \rightarrow \mathbb{R}$, $g : [0, T] \times \mathbb{R}^m \times A \rightarrow \mathbb{R}$, $\ell : [0, T] \times \mathbb{R}^m \times A \rightarrow [0, \infty)$ and $A \subset \mathbb{R}^k$. The conditions imposed on these functions are described in Section 2 below. The process $\{W_t\}_{0 \leq t \leq T}$ is a d -dimensional standard Brownian motion on a

probability space $(\Omega, \mathcal{F}, \mathbb{P})$ with a filtration $\{\mathcal{F}_t\}_{0 \leq t \leq T}$ satisfying the usual conditions. The class \mathcal{A} of controls is the collection of A -valued $\{\mathcal{F}_t\}_{0 \leq t \leq T}$ -progressively measurable processes $\{\alpha_t\}_{0 \leq t \leq T}$.

One of the main approaches for optimal stochastic control problems is to solve the Hamilton-Jacobi-Bellman (HJB) equation that the value function should satisfy, and then to construct a control strategy via the verification argument. For our problem (1.1), the corresponding HJB equation is given by

$$(1.3) \quad -\partial_t v + F(t, x, v, Dv, D^2v) = 0, \quad (t, x) \in [0, T] \times \mathbb{R}^m,$$

with the terminal condition $v(T, x) = f(x)$, $x \in \mathbb{R}^m$, where

$$F(t, x, r, p, M) = \sup_{a \in A} \left\{ -\mu(t, x, a)^\top p - \frac{1}{2} \text{tr}(\sigma(t, x, a) \sigma(t, x, a)^\top M) + r\ell(t, x, a) - g(t, x, a) \right\}$$

for $t \in [0, T]$, $x \in \mathbb{R}^m$, $r \in \mathbb{R}$, $p \in \mathbb{R}^m$, and M , a symmetric and nonnegative definite $m \times m$ matrix. Here we have denoted by ∂_t the partial differential operator with respect to the time variable t , by D^j the j -th order partial differential operator with respect to the space variable x , and by c^\top the transpose of a matrix c .

Since analytical solutions for HJB equations are rarely available, a number of authors have been concerned with approximation schemes for the equations or corresponding control problems. For example, Kushner and Dupuis [18], Camilli and Falcone [7], Pagès et al. [21], Fahim et al. [10], Kaise and McEneaney [14], and Kohn and Serfaty [15]. However, for practical applications there still remain several challenging problems. First one is that in some schemes the coefficients of the control problems have to be very restrictive for ensuring its convergence. For examples, in the finite-difference scheme (see [18]), the diffusion matrix $\sigma \sigma^\top$ in our notation should basically be diagonally dominant. Although this restriction can be weakened by considering the generalized finite-difference that involves a nontrivial adjustment of the diffusion matrix, we may need a large size of the stencil depending on a problem, as well as the further computational efforts for the implementation. See Bonnans and Zidani [5], Bonnans et al. [4] and the references therein. The optimal quantization approach taken by [21] works under mild conditions on the coefficients, in particular, under quadratic growth conditions on f and g . However, their scheme requires most components of the process $\{X_s^{t,x,\alpha}\}$ being actually control-free. In [10], they extract an uncontrolled generator from the nonlinearity F , and then use a probabilistic representation of the HJB equation based on the process associated with such generator. Then the partial derivatives of the value function in that representation are computed by the expectations of random variables involving the value function itself via the integration-by-parts. These tricks cost some strong non-degeneracy conditions on F .

Second problem is computational difficulties in high-dimensional cases. In general, the finite-difference scheme needs a spatial grid with its size growing exponentially as the dimension m becomes large. As for the method by [21], the quantization error with respect to an ν -dimensional random variable is known to be $O(N^{-1/\nu})$ if we denote by N the number of discretizing points for the random variable. The scheme by [10] can be applied to high-dimensional problems because it is based on Monte Carlo simulation for computing the conditional expectation, but the kernel density estimation used in this procedure is in general suffered from the

curse-of-dimensionality. The finite-element like schemes studied by e.g., [7] and Debrabant and Jakobsen [9], often called Semi-Lagrangian schemes, solve the first problem. That is, their scheme converge to the original value functions under no special assumption on the diffusion matrix $\sigma\sigma^\top$. The difficulty in their scheme is that they require the interpolation of the value functions in the state space, and need involved computational procedures for the implementation in high-dimensional problems (see Carlini et al. [8]).

In this paper, we propose a new time-discretization scheme for the problem (1.1). It is based on a probabilistic representation for the convolution of v by a probability density function. In Section 2 below, we first give a rough derivation of the semi-discrete scheme, and then prove its convergence results by the viscosity solution method presented in Barles and Souganidis [3]. With the choices of the kernel and with the estimation methods for the conditional expectations, various numerical methods can be generated. Resulting numerical methods allow us to use uncontrolled Markov processes to estimate the conditional expectations in the dynamic programming procedure. Moreover, they can be implemented without the interpolation of the value function or the adjustment of the diffusion matrix. We present one of possible methods with Gaussian distributions in Section 3. A numerical experiment is also performed there. We focus on an artificial problem having two-dimensional state space, where an analytical solution for (1.3) is easily obtained.

2 Approximation of the value function

First we introduce some notations. Throughout this paper, we write $|a| = (\sum_{i,j} a_{i,j}^2)^{1/2}$ for a matrix $a = (a_{i,j})$. By C we denote positive constants that may not be necessarily equal with each other.

We discuss the general stochastic control problem (1.1) under the following assumptions on the coefficients:

Assumption 2.1. (i) The functions μ, σ, f, g, ℓ are Borel measurable with respect to (t, x, a) and continuous with respect to (t, x) uniformly over a .

(ii) There exists a positive constant K such that, for every $s, t \in [0, T]$, $x, y \in \mathbb{R}^m$ and $a \in A$,

$$\begin{aligned} |\mu(t, x, a)| + |\sigma(t, x, a)| &\leq K(1 + |x|), \\ |\mu(s, x, a) - \mu(t, y, a)| + |\sigma(s, x, a) - \sigma(t, y, a)| &\leq K|s - t| + K|x - y|, \\ |f(x)| + |g(t, x, a)| + |\ell(t, x, a)| &\leq K. \end{aligned}$$

With these conditions, the controlled stochastic differential equation (1.2) has a unique strong solution for each control $\alpha \in \mathcal{A}$ (see, e.g., Fleming and Soner [11] or Krylov [16]) and the value function v in (1.1) becomes bounded. Moreover, it is known that v satisfies the viscosity solution property. To be precise, recall that an \mathbb{R} -valued, upper-semicontinuous function u on $[0, T] \times \mathbb{R}^m$ is said to be a viscosity subsolution of (1.3) if, for any $(t, x) \in [0, T] \times \mathbb{R}^m$ and any smooth function φ such that $u - \varphi$ has a local maximum at (t, x) we have

$$-\partial_t \varphi(t, x) + F(t, x, u(t, x), D\varphi(t, x), D^2\varphi(t, x)) \leq 0.$$

Similarly, an \mathbb{R} -valued, lower-semicontinuous function u on $[0, T] \times \mathbb{R}^m$ is said to be a viscosity supersolution of (1.3) if, for any $(t, x) \in [0, T] \times \mathbb{R}^m$ and any smooth function φ such that $u - \varphi$ has a local minimum at (t, x) we have

$$-\partial_t \varphi(t, x) + F(t, x, u(t, x), D\varphi(t, x), D^2\varphi(t, x)) \geq 0.$$

We say that u is a viscosity solution of (1.3) if it is both a viscosity subsolution and a viscosity supersolution of (1.3). Then, Theorem 4.3.1 in Pham [23] tells us that our value function v is indeed a viscosity solution of (1.3). In addition, by Theorem 4.4.5 in [23] the following comparison principle holds: for every bounded, upper-semicontinuous viscosity subsolution u of (1.3) and bounded lower-semicontinuous viscosity supersolution w of (1.3) such that $u(T, x) \leq w(T, x)$, $x \in \mathbb{R}^m$, we have

$$u(t, x) \leq w(t, x), \quad (t, x) \in [0, T] \times \mathbb{R}^m.$$

Let $\{t_i\}_{i=0}^n$ be a fixed set of time indices such that $0 = t_0 < t_1 < \dots < t_n = T$ with $h = t_i - t_{i-1} = T/n$, $i = 1, \dots, n$. We consider n sufficiently large so that $h \in (0, 1]$. To find a time discretization scheme for the value function, first we write down the dynamic programming principle as follows:

$$\begin{aligned} & v(t_i, x) \\ &= \inf_{\alpha \in \mathcal{A}} \mathbb{E} \left[v(t_{i+1}, X_{t_{i+1}}^{t_i, x, \alpha}) e^{-\int_{t_i}^{t_{i+1}} \ell(s, X_s^{t_i, x, \alpha}, \alpha_s) ds} + \int_{t_i}^{t_{i+1}} g(s, X_s^{t_i, x, \alpha}, a_s) e^{-\int_{t_i}^s \ell(r, X_r^{t_i, x, \alpha}, \alpha_r) dr} ds \right]. \end{aligned}$$

Replacing $X_{t_{i+1}}^{t_i, x, \alpha}$ by its Euler-Maruyama approximation $\hat{X}_{t_{i+1}}^{t_i, x, a}$ defined by

$$\hat{X}_s^{t, x, a} = x + \mu(t, x, a)(s - t) + \sigma(t, x, a)\sqrt{s - t}G, \quad t \leq s \leq t + h, \quad a \in A,$$

formally we have

$$\begin{aligned} & \mathbb{E} \left[v(t_{i+1}, X_{t_{i+1}}^{t_i, x, \alpha}) e^{-\int_{t_i}^{t_{i+1}} \ell(s, X_s^{t_i, x, \alpha}, \alpha_s) ds} + \int_{t_i}^{t_{i+1}} g(s, X_s^{t_i, x, \alpha}, \alpha_s) e^{-\int_{t_i}^s \ell(r, X_r^{t_i, x, \alpha}, \alpha_r) dr} ds \right] \\ & \approx \mathbb{E} \left[v(t_{i+1}, \hat{X}_{t_{i+1}}^{t_i, x, \alpha_i}) \right] e^{-h\ell(t_i, x, \alpha_i)} + hg(t_i, x, \alpha_i). \end{aligned}$$

Here, $G = (G_1, \dots, G_d)^*$ is a random variable such that G_i 's are mutually independent and that

$$(2.1) \quad \mathbb{E}[G_i] = 0, \quad \mathbb{E}[G_i G_j] = \delta_{ij}, \quad \mathbb{E}[|G_i|^3] < \infty, \quad i, j = 1, \dots, d,$$

where δ_{ij} denotes the Kronecker's delta.

Now we consider the convolution $\phi^h * v(t_{i+1}, \cdot)$ by some kernel ϕ^h to approximate $v(t_{i+1}, \cdot)$. To this end, let ϕ be a probability density function on \mathbb{R}^m with full support and finite first moment, i.e., $\phi(y) > 0$ for all $y \in \mathbb{R}^m$ and

$$\int_{\mathbb{R}^m} |z| \phi(z) dz < \infty.$$

Then define

$$\phi^h(x) := \frac{\phi(x/\lambda(h))}{\lambda(h)^m}, \quad x \in \mathbb{R}^m,$$

where λ is a positive function on $(0, 1]$. Then, for any bounded function u , the convolution $\phi^h * u$ can be represented as

$$\begin{aligned} (\phi^h * u)(x + \xi) &= \int_{\mathbb{R}^m} u(z) \frac{\phi((x + \xi - z)/\lambda(h))}{\lambda(h)^m} dz \\ &= \int_{\mathbb{R}^m} u(x + \lambda(h)z) \phi\left(\frac{\xi}{\lambda(h)} - z\right) dz, \quad x, \xi \in \mathbb{R}^m. \end{aligned}$$

Let \mathcal{D}^h be a subset of \mathbb{R}^m satisfying $\sup_{\xi \in \mathbb{R}^m} \int_{\mathbb{R}^m \setminus \mathcal{D}^h} \phi(\xi/\lambda(h) - z) dz \rightarrow 0$, $h \searrow 0$, and let ψ^h be an another probability density function having \mathcal{D}^h as the support set. Then, roughly speaking, $(\phi^h * u)(x + \xi)$ is approximated by $\int_{\mathcal{D}^h} u(x + \lambda(h)z) \phi(\xi/\lambda(h) - z) dz$ and this can be written as

$$\begin{aligned} \int_{\mathcal{D}^h} u(x + \lambda(h)z) \phi\left(\frac{\xi}{\lambda(h)} - z\right) dz &= \int_{\mathcal{D}^h} u(x + \lambda(h)z) \phi\left(\frac{\xi}{\lambda(h)} - z\right) \frac{\psi^h(z)}{\psi^h(z)} dz \\ &= \mathbb{E} \left[u(x + \lambda(h)Z^h) \phi\left(\frac{\xi}{\lambda(h)} - Z^h\right) \frac{1}{\psi^h(Z^h)} \right], \end{aligned}$$

where Z^h is a random variable with probability density ψ^h , which is assumed to be independent of G . Thus, denoting $H_h^{t,x,a} = \mu(t, x, a)h + \sigma(t, x, a)\sqrt{h}G$, we have

$$\begin{aligned} \mathbb{E} \left[(\phi^h * u)(\hat{X}_{t+h}^{t,x,a}) \right] &\approx \mathbb{E} \left[\mathbb{E} \left[u(x + \lambda(h)Z^h) \phi\left(\frac{H_h^{t,x,a}}{\lambda(h)} - Z^h\right) \frac{1}{\psi^h(Z^h)} \middle| H_h^{t,x,a} \right] \right] \\ &= \mathbb{E} \left[u(x + \lambda(h)Z^h) \phi\left(\frac{H_h^{t,x,a}}{\lambda(h)} - Z^h\right) \frac{1}{\psi^h(Z^h)} \right]. \end{aligned}$$

The last expression might be useful since the argument of u is control-free. Then, as $\lambda(h) \searrow 0$, the quantity $\mathbb{E}[(\phi^h * u)(\hat{X}_{t+h}^{t,x,a})]$ converges to $\mathbb{E}[u(\hat{X}_{t+h}^{t,x,a})]$ under mild conditions on u , so we expect that the scheme defined by

$$\begin{cases} v^h(T, x) = f(x), \\ v^h(t_i, x) = \Phi^h[v^h(t_{i+1}, \cdot)](t_i, x) \end{cases}$$

with

$$\begin{aligned} &\Phi^h[u](t, x) \\ &= \inf_{a \in A} \left\{ \mathbb{E} \left[u(x + \lambda(h)Z^h) \phi\left(\frac{H_h^{t,x,a}}{\lambda(h)} - Z^h\right) \frac{1}{\psi^h(Z^h)} \right] e^{-h\ell(t,x,a)} + hg(t, x, a) \right\} \end{aligned}$$

gives an approximation for the value function v .

Let β be a function on $(0, 1]$ defined by

$$(2.2) \quad \beta(h) = \sup_{\substack{t \in [0, T], \\ \xi \in \mathbb{R}^m \\ a \in A}} \mathbb{E} \int_{\mathbb{R}^m \setminus \mathcal{D}^h} \phi\left(\frac{H_h^{t,\xi,a}}{\lambda(h)} - z\right) dz.$$

Then we are able to state the following convergence result.

Theorem 2.2. Let $v : [0, T] \times \mathbb{R}^m \rightarrow \mathbb{R}$ be defined by (1.1). Suppose that Assumption 2.1 is satisfied. Suppose also that

$$\lim_{h \searrow 0} \frac{\lambda(h) + \beta(h)}{h} = 0.$$

Then,

$$v^h(t_i, x) \longrightarrow v(t, x)$$

as $h \searrow 0$, and $t_i \rightarrow t$, uniformly on any compact subset of \mathbb{R}^m .

Proof. First, the functions ϕ and ψ^h are positive, so we have

$$(2.3) \quad \Phi^h[u_1](t, x) \leq \Phi^h[u_2](t, x)$$

for bounded functions u_1, u_2 with $u_1 \leq u_2$.

Next, it is straightforward to see that

$$\begin{aligned} |v^h(t_i, x)| &\leq \sup_{a \in A} \mathbb{E} \int_{\mathbb{R}^m} |v^h(t_{i+1}, \hat{X}_{t_{i+1}}^{t_i, x, a} + \xi)| \phi^h(\xi) d\xi + h \sup_{a \in A} |g(t_i, x, a)| \\ &\leq \sup_{x' \in \mathbb{R}^m} |v^h(t_{i+1}, x')| + h \sup_{a \in A} |g(t_i, x, a)|. \end{aligned}$$

Thus, by Assumption 2.1,

$$(2.4) \quad |v^h(t_i, x)| \leq (1 + T)K, \quad h \in (0, 1], \quad x \in \mathbb{R}^m, \quad i = 0, 1, \dots, n.$$

Let u be a smooth function with bounded derivatives. Then,

$$(2.5) \quad \begin{aligned} &\left| \frac{1}{h} \left\{ \Phi^h[u(s+h, \cdot)](s, y) - u(s, y) \right\} - \left\{ \partial_t u(t, x) - F(t, x, u(t, x), Du(t, x), D^2 u(t, x)) \right\} \right| \\ &\leq \frac{1}{h} \left| \Phi^h[u(s+h, \cdot)](s, y) - \inf_{a \in A} \mathbb{E} \left[u(s+h, \hat{X}_{s+h}^{s, y, a}) e^{-h\ell(s, y, a)} + hg(s, y, a) \right] \right| + \\ &\left| \frac{1}{h} \left\{ \inf_{a \in A} \mathbb{E} \left[u(s+h, \hat{X}_{s+h}^{s, y, a}) e^{-h\ell(s, y, a)} + hg(s, y, a) \right] - u(s, y) \right\} \right. \\ &\quad \left. - \left\{ \partial_t u(t, x) - F(t, x, u(t, x), Du(t, x), D^2 u(t, x)) \right\} \right|. \end{aligned}$$

Since u has bounded derivatives, the first term of the right-hand side in (2.5) is at most

$$\begin{aligned} &\frac{1}{h} \sup_{a \in A} \mathbb{E} \left[\left| \left(\phi^h * u(s+h, \cdot) \right) (\hat{X}_{s+h}^{s, y, a}) - u(s+h, \hat{X}_{s+h}^{s, y, a}) \right| \right. \\ &\quad \left. + \int_{\mathbb{R}^m \setminus \mathcal{D}^h} |u(s+h, y + \lambda(h)z)| \phi \left(\frac{H_h^{s, y, a}}{\lambda(h)} - z \right) dz \right] \\ &\leq \frac{1}{h} \mathbb{E} \int_{\mathbb{R}^m} |u(s+h, \hat{X}_{s+h}^{s, y, a} + \lambda(h)z) - u(s+h, \hat{X}_{s+h}^{s, y, a})| \phi(z) dz + \frac{C}{h} \beta(h) \\ &\leq C \frac{1}{h} (\lambda(h) + \beta(h)). \end{aligned}$$

On the other hand, by Assumption 2.1 and by the standard application of Taylor's theorem, we see that the second term of the right-hand side in (2.5) converges to zero as $(s, y) \rightarrow (t, x)$ and $h \searrow 0$. Moreover, we find that

$$|\Phi^h[u(s+h, \cdot) + c](s, y) - \Phi^h[u(s+h, \cdot)](s, y) - c| \leq |c|\beta(h)$$

for every $c \in \mathbb{R}$. Therefore, for $(t, x) \in [0, T) \times \mathbb{R}^m$,

$$(2.6) \quad \lim_{\substack{(s,y) \rightarrow (t,x) \\ c \rightarrow 0, h \searrow 0}} \frac{1}{h} \left[\Phi^h[u(s+h, \cdot) + c](s, y) - (u(s, y) + c) \right] \\ = \partial_t u(t, x) - F(t, x, u(t, x), Du(t, x), D^2 u(t, x)).$$

Next, notice that

$$|v^h(T-h, x+z) - f(x)| \\ \leq \mathbb{E} \int_{\mathbb{R}^m} \sup_{a \in A} \left| f \left(\hat{X}_T^{T-h, x+z, a} + \lambda(h)\xi \right) e^{-h\ell(T-h, x+z, a)} - f(x) \right| \phi(\xi) d\xi + Kh.$$

Then, for fixed $\xi \in \mathbb{R}^m$ and $\omega \in \Omega$, it follows from Assumption 2.1 that $\hat{X}_T^{T-h, x+z, a}(\omega) + \lambda(h)\xi$ lies in a compact set in \mathbb{R}^m that is independent of a for sufficiently small h and $|z|$. So the continuity of f implies that

$$\sup_{a \in A} \left| f \left(\hat{X}_T^{T-h, x+z, a}(\omega) + \lambda(h)\xi \right) e^{-h\ell(T-h, x+z, a)} - f(x) \right| \rightarrow 0, \quad h \searrow 0, \quad z \rightarrow 0.$$

Hence, by the dominated convergence theorem we obtain

$$(2.7) \quad \lim_{h \searrow 0, y \rightarrow x} v^h(T-h, y) = f(x), \quad x \in \mathbb{R}^m.$$

We have verified the monotonicity (2.3), the stability (2.4), the consistency (2.6), and (2.7). With these properties and the comparison principle, we can apply the viscosity solution method as stated in [3] to prove our convergence result. Here, for completeness we give a full proof of the convergence. To this end, we consider

$$\bar{v}(t, x) = \limsup_{\substack{(s,y) \rightarrow (t,x) \\ h \searrow 0}} v^h(s, y), \quad (t, x) \in [0, T) \times \mathbb{R}^m$$

and show that \bar{v} is a viscosity subsolution of (1.3). Let φ be a smooth function with bounded derivatives such that $\bar{v} - \varphi$ has a local maximum at $(t, x) \in [0, T) \times \mathbb{R}^m$. Then, take $r > 0$ such that

$$(\bar{v} - \varphi)(s, y) \leq (\bar{v} - \varphi)(t, x), \quad (s, y) \in B_r(t, x).$$

where $B_r(t, x)$ denote the closed ball at (t, x) with radius r . Next, for $(s, y) \in B_r(t, x)$ set

$$\tilde{\varphi}(s, y) = \varphi(s, y) - (\varphi(t, x) - \bar{v}(t, x)) + |s-t|^2 + |y-x|^2.$$

It follows that (t, x) is a strict maximum of $\bar{v} - \tilde{\varphi}$ on $B_r(t, x)$. Also, for (s, y) outside the ball, we choose $\tilde{\varphi}$ so that $\tilde{\varphi}(s, y) \geq 2 \sup_{h \in (0, 1]} |v^h(s, y)|$ and that $\tilde{\varphi}$ is still a smooth function on $[0, T) \times \mathbb{R}^m$

with bounded derivatives. Thus (t, x) is a global strict maximum of $\bar{v} - \bar{\varphi}$. By abuse of notation, we write φ for $\bar{\varphi}$.

By definition of \bar{v} , there exist $h_N, (\tilde{s}_N, \tilde{y}_N) \in B_r(t, x)$ such that, as $N \rightarrow \infty$,

$$h_N \rightarrow 0, \quad (\tilde{s}_N, \tilde{y}_N) \rightarrow (t, x), \quad v^{h_N}(\tilde{s}_N, \tilde{y}_N) \rightarrow \bar{v}(t, x).$$

Take s_N and y_N so that

$$(2.8) \quad (v^{h_N} - \varphi)(s_N, y_N) \geq \sup_{(s, y) \in [0, T] \times \mathbb{R}^m} (v^{h_N} - \varphi)(s, y) - h_N^2.$$

The sequence (s_N, y_N) , $N \geq 1$, can be taken from the bounded set $B_r(t, x)$, so there exists a limit point $(\tilde{t}, \tilde{x}) \in B_r(t, x)$ possibly along a subsequence. Thus, denoting $c_N = (v^{h_N} - \varphi)(s_N, y_N)$, we have

$$0 = (\bar{v} - \varphi)(t, x) = \lim_{N \rightarrow \infty} (v^{h_N} - \varphi)(\tilde{s}_N, \tilde{y}_N) \leq \liminf_{N \rightarrow \infty} c_N \leq \limsup_{N \rightarrow \infty} c_N \leq (\bar{v} - \varphi)(\tilde{t}, \tilde{x}).$$

Since (t, x) is a strict maximum, we deduce that $(\tilde{t}, \tilde{x}) = (t, x)$. Therefore, it follows that $(s_N, y_N) \rightarrow (t, x)$ and $c_N \rightarrow 0$.

By (2.8), for any $y \in \mathbb{R}^m$,

$$\varphi(s_N + h_N, y) + c_N + h_N^2 \geq v^{h_N}(s_N + h_N, y).$$

Thus, using the monotonicity (2.3),

$$\begin{aligned} \frac{1}{h_N} \Phi^{h_N}[\varphi(s_N + h_N, \cdot) + c_N + h_N^2](s_N, y_N) &\geq \frac{1}{h_N} v^{h_N}(s_N, y_N) \\ &= \frac{1}{h_N} (\varphi(s_N, y_N) + c_N + h_N^2) - h_N. \end{aligned}$$

Combining this with the consistency (2.6), we find that

$$\partial_t \varphi - F(t, x, \varphi, D\varphi, D^2\varphi) \geq 0.$$

This means the subsolution property of \bar{v} .

By a similar argument, we can show that

$$\underline{v}(t, x) = \liminf_{\substack{(s, y) \rightarrow (t, x) \\ h \searrow 0}} v^h(s, y), \quad (t, x) \in [0, T] \times \mathbb{R}^m$$

is a viscosity supersolution of (1.3). The comparison principle now implies that $\bar{v} \leq \underline{v}$. However, by definition, $\bar{v} \geq \underline{v}$. Hence we obtain $\bar{v} = \underline{v}$, as asserted. \square

To obtain the rates of convergence of our schemes, we impose more regularity conditions on the coefficients.

Assumption 2.3. There exist positive constants K' such that, for every $s, t \in [0, T]$, $x, y \in \mathbb{R}^m$ and $a \in A$,

$$\begin{aligned} |f(x) - f(y)| + |g(s, x, a) - g(t, y, a)| + |\ell(s, x, a) - \ell(t, y, a)| &\leq K'|x - y| + K'|s - t|^{1/2}, \\ |\mu(t, x, a)| &\leq K', \quad |\sigma(t, x, a)| \leq K'. \end{aligned}$$

Theorem 2.4. Let $v : [0, T] \times \mathbb{R}^m \rightarrow \mathbb{R}$ be defined by (1.1). Suppose that Assumptions 2.1 and 2.3 are satisfied. Suppose also that $\mathbb{E}[G_i^3] = 0$, $\mathbb{E}[G_i^4] < \infty$, $i = 1, \dots, d$. If λ and β satisfy $\lambda(h) + \beta(h) \leq Ch^{7/6}$, then we have

$$\max_{0 \leq i \leq n} |v^h(t_i, x) - v(t_i, x)| \leq Ch^{1/6}, \quad x \in \mathbb{R}^m.$$

Furthermore, if $\lambda(h) + \beta(h) \leq Ch^{3/2}$ then we obtain

$$-Ch^{1/6} \leq v(t_i, x) - v^h(t_i, x) \leq Ch^{1/4}, \quad x \in \mathbb{R}^m, \quad i = 0, 1, \dots, n.$$

Proof. To show the first assertion, let λ and β satisfy $\lambda(h) + \beta(h) \leq Ch^{7/6}$. We consider the another scheme \bar{v}^h defined by, for $x \in \mathbb{R}^d$,

$$\begin{cases} \bar{v}^h(t_i, x) = \inf_{a \in A} \mathbb{E} \left[\bar{v}^h(\hat{X}_{t_{i+1}}^{t_i, x, a}) e^{-h\ell(t_i, x, a)} + hg(t_i, x, a) \right], & i = 0, 1, \dots, n-1, \\ \bar{v}^h(T, x) = f(x). \end{cases}$$

Then, by Theorem 5.7 in Krylov [17], we have

$$|v(t, x) - \bar{v}^h(t, x)| \leq Ch^{1/6}.$$

Moreover, Lemma 5.8 in [17] implies that, for every $\varepsilon > 0$ we can find a function $u^{h, \varepsilon}$ on $[0, T] \times \mathbb{R}^m$ satisfying

$$|u^{h, \varepsilon}(t, x) - u^{h, \varepsilon}(t, y)| \leq C|x - y|, \quad |u^{h, \varepsilon}(t_i, x) - \bar{v}^h(t_i, x)| \leq C\varepsilon.$$

In view of these facts, we see

$$\begin{aligned} |v(t_i, x) - v^h(t_i, x)| &\leq |v(t_i, x) - \bar{v}^h(t_i, x)| + |v^h(t_i, x) - \bar{v}^h(t_i, x)| \\ &\leq Ch^{1/6} + \sup_{a \in A} \mathbb{E} \int_{\mathbb{R}^d} |v^h(t_{i+1}, \hat{X} + \lambda(h)\xi) - \bar{v}^h(t_{i+1}, \hat{X})| \phi(\xi) d\xi \\ &\quad + \sup_{a \in A} \mathbb{E} \int_{\mathbb{R}^d \setminus \mathcal{D}^h} |v^h(t_{i+1}, x + \lambda(h)\xi)| \phi\left(\frac{H_h^{x, a}}{\lambda(h)} - \xi\right) d\xi \\ &\leq Ch^{1/6} + \sup_{a \in A} \mathbb{E} \int_{\mathbb{R}^d} \left\{ |v^h(t_{i+1}, \hat{X} + \lambda(h)\xi) - \bar{v}^h(t_{i+1}, \hat{X} + \lambda(h)\xi)| \right. \\ &\quad \left. + |u^{h, \varepsilon}(t_{i+1}, \hat{X} + \lambda(h)\xi) - u^{h, \varepsilon}(t_{i+1}, \hat{X})| + C\varepsilon \right\} \phi(\xi) d\xi + C\beta(h) \\ &\leq Ch^{1/6} + \sup_{y \in \mathbb{R}^d} |v^h(t_{i+1}, y) - \bar{v}^h(t_{i+1}, y)| + C(\lambda(h) + \varepsilon + \beta(h)). \end{aligned}$$

Here, we have denoted $\hat{X} = \hat{X}_{t_{i+1}}^{t_i, x, a}$. Repeating these arguments, we have, for any $i = 0, 1, \dots, n$ and $x \in \mathbb{R}^m$

$$|v(t_i, x) - v^h(t_i, x)| \leq Ch^{1/6} + C(\lambda(h) + \varepsilon + \beta(h))/h.$$

Taking $\varepsilon \leq h^{7/6}$, we obtain the desired result.

To prove the second claim, let λ and β satisfy $\lambda(h) + \beta(h) \leq Ch^{3/2}$, and let $\zeta(t, x)$ be a C^∞ positive function on \mathbb{R}^{m+1} with support set $[0, 1] \times \{x \in \mathbb{R}^m : |x| \leq 1\}$ and with unit integral.

Proposition 2.1 in Barles and Jakobsen [2] tells us that v is actually Lipschitz in x and $1/2$ -Hölder continuous in t . For a given $\varepsilon > 0$, we consider the function ζ^ε and w^ε defined by

$$\zeta^\varepsilon(t, x) = \varepsilon^{-m-2} \zeta(\varepsilon^{-2}t, \varepsilon^{-1}x), \quad w^\varepsilon(t, x) = (v * \zeta^\varepsilon)(t, x).$$

Then,

$$(2.9) \quad |v(t, x) - w^\varepsilon(t, x)| \leq C\varepsilon, \quad |\partial_t^{\ell_0} \partial_{x_1}^{\ell_1} \cdots \partial_{x_m}^{\ell_m} w^\varepsilon(t, x)| \leq C\varepsilon^{1-2\ell_0-\sum_{i=1}^m \ell_i},$$

where ∂_y^ℓ denotes the ℓ -th order partial differential operator with respect to a variable y . Using these facts and the moment conditions on G , we can show that, as in the proof of the previous theorem,

$$(2.10) \quad \left| \frac{\Phi^h[w^\varepsilon(t+h, \cdot)](t, x) - w^\varepsilon(t, x)}{h} - \partial_t w^\varepsilon(t, x) + F(t, x, w^\varepsilon(t, x), Dw^\varepsilon(t, x), D^2 w^\varepsilon(t, x)) \right| \\ \leq C \frac{\lambda(h) + \beta(h)}{h\varepsilon} + C \frac{h}{\varepsilon^3} \leq C \frac{h^{1/2}}{\varepsilon} + C \frac{h}{\varepsilon^3}.$$

In addition, it follows from the appendix in Barles and Jakobsen [1] that w^ε is a subsolution of (1.3). This and (2.10) imply

$$(2.11) \quad w^\varepsilon(t_i, x) - \Phi^h[w^\varepsilon(t_{i+1}, \cdot)](t_i, x) \\ \leq w^\varepsilon(t_i, x) \\ - \Phi^h[w^\varepsilon(t_{i+1}, \cdot)](t_i, x) + \partial_t w^\varepsilon(t_i, x) - F(t_i, x, w^\varepsilon(t_i, x), Dw^\varepsilon(t_i, x), D^2 w^\varepsilon(t_i, x)) \\ \leq C \frac{h^{3/2}}{\varepsilon} + C \frac{h^2}{\varepsilon^3}.$$

Since $v^h(T, x) = v(T, x)$, from (2.9) we have $w^\varepsilon(T, x) \leq v^h(T, x) + C\varepsilon$. Taking Φ^h in the both side, we obtain

$$\Phi^h[w^\varepsilon(T, \cdot)] \leq v^h(t_{n-1}, x) + C\varepsilon.$$

Combining this with (2.11), we have

$$w^\varepsilon(t_{n-1}, x) \leq v^h(t_{n-1}, x) + C\varepsilon + C \frac{h^{3/2}}{\varepsilon} + C \frac{h^2}{\varepsilon^3}.$$

Repeating this argument, we deduce that, for $i = 0, \dots, n$,

$$w^\varepsilon(t_i, x) \leq v^h(t_i, x) + C\varepsilon + C \frac{h^{1/2}}{\varepsilon} + C \frac{h}{\varepsilon^3}.$$

Therefore, by (2.9), for any $i = 0, \dots, n$ and $x \in \mathbb{R}^m$,

$$v(t_i, x) - v^h(t_i, x) \leq v(t_i, x) - w^\varepsilon(t_i, x) + w^\varepsilon(t_i, x) - v^h(t_i, x) \leq C \left(\varepsilon + \frac{h^{1/2}}{\varepsilon} + \frac{h}{\varepsilon^3} \right).$$

Then, the minimization of the right-hand side over $\varepsilon > 0$ gives $v(t_i, x) - v^h(t_i, x) \leq Ch^{1/4}$, as required. \square

3 A fully numerical method

Throughout this section, we suppose that Assumptions 2.1 and 2.3 are satisfied. We take the \mathbb{R}^d -valued random variable $G = G^{M,q}$ as an optimally quantized random variable in the sense that $G^{M,q}$ is a minimizer of

$$\mathbb{E}[|X - G|^q]$$

over finite random variables G with M -supporting points, where $q \geq 1$ and X is a d -dimensional standard Gaussian random variable. We refer to Graf and Luschgy [12] for a detailed account of optimal quantization theory, and to Pagés and Printems [22] for numerical procedures for obtaining $G^{M,2}$. Set

$$G^{M,q}(\Omega) = \{\gamma_1, \dots, \gamma_M\}, \quad \mathbb{P}(G^{M,q} = \gamma_i) = p_i, \quad i = 1, \dots, M.$$

In most of numerical realizations, the random variables $G^{M,q}$'s approximately satisfy the moment condition (2.1). A reason why we use the quantization is that we need sufficiently many points of $H_h^{t,x,a}/\lambda(h)$'s near its mean to be shot by Monte Carlo simulations of Gaussian random variables, with less number of computations. See the comment made just after (3.2) below.

We choose the function λ as

$$\lambda(h)/h \rightarrow 0, \quad h \searrow 0.$$

For example, we may take $\lambda(h) = h/(-\log h)$.

To describe the realizations of $H_h^{t,x,a}$, we put

$$\eta_i^h(t, x, a) = \mu(t, x, a)h + \sigma(t, x, a)\sqrt{h}\gamma_i, \quad i = 1, \dots, M.$$

As the functions ϕ and ψ^h , we examine

$$\phi(y) = \frac{e^{-|y|^2/2}}{(2\pi)^{m/2}}, \quad \psi^h(y) = \frac{e^{-|y|^2/(2\tau(h))}}{(2\pi\tau(h))^{m/2}}, \quad y \in \mathbb{R}^m,$$

where $\tau(h) > 0$.

Let Z be an m -dimensional standard Gaussian random variable. Then, we consider the operator $\hat{\Phi}^h[u]$ approximating $\Phi^h[u]$, defined by

$$\hat{\Phi}^h[u](t, x) = \inf_{a \in A} \left\{ \sum_{j=1}^M p_j \mathbb{E} \left[u \left(x + \lambda(h) \sqrt{\tau(h)} Z \right) \phi \left(\frac{\eta_j^h(t, x, a)}{\lambda(h)} - \sqrt{\tau(h)} Z \right) \right. \right. \\ \left. \left. \times \frac{e^{-h\ell(t, x, a)}}{\psi^h(\sqrt{\tau(h)} Z)} \right] + hg(t, x, a) \right\}.$$

Here, $\theta(h)$ is a positive function on $(0, 1]$ such that $\theta(h) \rightarrow \infty$ as $h \searrow 0$. Furthermore, we introduce the uncontrolled Markov process $\{S_k\}_{k=0}^n$ defined by

$$S_{k+1} = S_k + \lambda(h) \sqrt{\tau(h)} Z_{k+1}, \quad k = 0, \dots, n-1,$$

where $\{Z_k\}_{k=1}^n$ denote an i.i.d. sequence with $Z_1 \sim Z$. With this process, $\hat{\Phi}^h[u]$ can be written as

$$(3.1) \quad \hat{\Phi}^h[u](t_k, x) = \inf_{a \in A} \left\{ \tau(h)^{m/2} \sum_{i=1}^M p_i \mathbb{E} \left[u(S_{k+1}) \exp \left(-\frac{1}{2} \left| \frac{\eta_i^h(t_k, x, a)}{\lambda(h)} - \sqrt{\tau(h)} Z_{k+1} \right|^2 + \frac{1}{2} |Z_{k+1}|^2 - h\ell(t_k, x, a) \right) \middle| S_k = x \right] + hg(t_k, x, a) \right\}.$$

To compute the conditional expectation in (3.1), we use the kernel density estimators with samples from Monte Carlo simulation. We refer to Longstaff and Schwartz [20], a landmark study of this approach in American option pricing, and to Bouchard and Touzi [6] and Lemor et al. [19] in the context of backward stochastic differential equations. It should be mentioned that this regression method is also adopted in [10] for the numerical study of HJB equations.

In our framework, an estimator $\hat{\mathbb{E}}^N[Y | S_k = x]$ for $\mathbb{E}[Y | S_k = x]$ can be taken as

$$\hat{\mathbb{E}}^N[Y | S_k = x] = \frac{\sum_{j=1}^N Y^{(j)} \kappa \left(\frac{x - S_k^{(j)}}{\Delta} \right)}{\sum_{j=1}^N \kappa \left(\frac{x - S_k^{(j)}}{\Delta} \right)}$$

if the denominator is nonzero. Otherwise the estimator is defined as zero. Here,

$$Y = u(S_{k+1}) \exp \left(-\frac{1}{2} \left| \frac{\eta_j^h(t_k, x, a)}{\lambda(h)} - \sqrt{\tau(h)} Z_{k+1} \right|^2 + \frac{1}{2} |Z_{k+1}|^2 \right),$$

$Y^{(1)}, \dots, Y^{(N)}, Z_k^{(1)}, \dots, Z_k^{(N)}$, and $S_k^{(1)}, \dots, S_k^{(N)}$ are samples from Monte Carlo simulations for Y , Z_k , and S_k respectively, and Δ denotes the bandwidth for the kernel function κ . A typical example for κ is the naive kernel defined by

$$\kappa(z) = 1_{\{|z| \leq 1\}}, \quad z \in \mathbb{R}^m.$$

We refer to Györfi et al. [13] for other estimators and its convergence analyses.

Consequently, our scheme can be implemented as follows: $V_n^{(\nu)} = f(S_n^{(\nu)})$, $\nu = 1, \dots, N$, and

$$(3.2) \quad V_k^{(\nu)} = \inf_{a \in A} \left\{ \tau(h)^{m/2} \sum_{i=1}^M p_i \sum_{j=1}^N V_{k+1}^{(j)} \exp \left(-\frac{1}{2} \left| \frac{\eta_i^h(t_k, S_k^{(\nu)}, a)}{\lambda(h)} - \sqrt{\tau(h)} Z_{k+1}^{(j)} \right|^2 + \frac{1}{2} |Z_{k+1}^{(j)}|^2 - h\ell(t_k, S_k^{(\nu)}, a) \right) \kappa \left(\frac{S_k^{(\nu)} - S_k^{(j)}}{\Delta} \right) / \sum_{j=1}^N \kappa \left(\frac{S_k^{(\nu)} - S_k^{(j)}}{\Delta} \right) + hg(t_k, S_k^{(\nu)}, a) \right\}, \quad \nu = 1, \dots, N, \quad k = 0, \dots, n-1.$$

We note that in general we need to set $\tau(h)$ large so that the values

$$\exp\left(-\frac{1}{2}\left|\frac{\eta_i^h(t_k, S_k^{(v)}, a)}{\lambda(h)} - \sqrt{\tau(h)}Z^{(j)}\right|^2\right)$$

actually contribute to the computation of $V_k^{(v)}$.

As for control strategies, a minimizer $a_k^{(v)}$ of the right-hand side in (3.2) is a numerically optimal control at $(t_k, S_k^{(v)})$. In case one needs the values of reasonable control at given grids, the average values of $a_k^{(v)}$ distributed around the each grid point can be used.

Example 3.1. As an illustration of our scheme, we examine the test problem described by

$$\begin{aligned} T = 0.1, \quad d = 1, \quad m = 2, \quad A = \{a = (a_1, a_2)^* \in \mathbb{R}^2 : a_1^2 + a_2^2 = 1\}, \\ \mu(t, x) = 0, \quad \sigma(t, x, a) = \sqrt{2}(a_1, a_2)^*, \\ f(x) = (1 + T)T \sin x_1 \sin x_2, \quad \ell(t, x, a) = 0, \\ g(t, x, a) = -2(1 + t)Ta_1a_2 \cos x_1 \cos x_2 + tT \sin x_1 \sin x_2 \end{aligned}$$

for $t \in [0, T]$, $x = (x_1, x_2)^*$, and $a = (a_1, a_2)^* \in A$. This example is adopted in [9]. It is straightforward to see that the value function v in this problem is explicitly given by

$$v(t, x) = (1 + t)T \sin x_1 \sin x_2,$$

and that any point in A is an optimal control.

In implementing our numerical method (3.2), we take $h = 0.01$, and set $\lambda(h) = h/(-\log(h))$ and $\tau(h) = (\sqrt{2h}/\lambda(h))^2$. With this choice we can expect that Monte Carlo paths shoot most realization of η_i 's since the set $\{\eta_i(t_k, x, a) : x \in \mathbb{R}^m, a \in A\}$ is included in $\{y \in \mathbb{R}^m : |y| \leq \sqrt{2h}\gamma_i\}$. We use $N = 3 \times 10^6$ samples to estimate the kernel density with the naive kernel and $\Delta = 0.1$. The quadratic quantization with $M = 100$ points is adopted for $G^{(M, q)}$. The initial value of the controlled process is set to be $(\pi/2, \pi/2)^*$. The resulting average absolute error between $V_k^{(\ell)}$ and $v(t_k, S_k^{(\ell)})$, $\ell = 1, \dots, N$, at $k = 9$ is 0.0064.

Figure 3.1 compares $v(t_k, x)$ and an estimated value function using $V_k^{(\ell)}$'s at $k = 9$. We use the average values of $V_k^{(\ell)}$'s in suitable clusters to estimate the value function at uniform grid points. The figure indicates that our method on the whole underestimates the analytical solution. This may be because the number of Monte Carlo paths shooting $\eta_i^h(t_k, S_k^{(\ell)}, a)/\lambda(h)$'s is still insufficient.

Acknowledgements

The author is thankful to Takashi Tamura for helpful comments, as well as the anonymous referee for his/her careful reading of a previous version of this paper.

This study is partially supported by Grant-in-Aid for Young Scientists (B) (Grant No. 23740069) from JSPS.

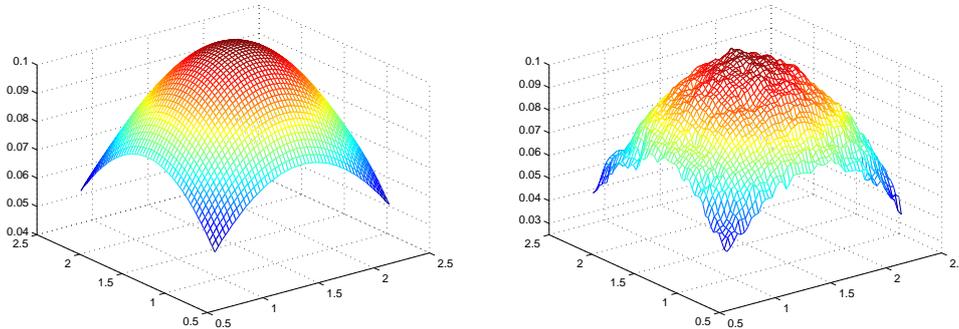


Figure 3.1: The analytical (left) and estimated (right) value functions at $t = 0.09$ around $x = (\pi/2, \pi/2)^*$.

References

- [1] G. Barles and E. R. Jakobsen. On the convergence rate of approximation schemes for Hamilton-Jacobi-Bellman equations. *Math. Model. Numer. Anal.*, 36:33–54, 2002.
- [2] G. Barles and E. R. Jakobsen. Error bounds for monotone approximation schemes for parabolic Hamilton-Jacobi-Bellman equations. *Math. Comp.*, 76:1861–1893, 2007.
- [3] G. Barles and P. E. Souganidis. Convergence of approximation schemes for fully nonlinear second order equations. *Asymptot. Anal.*, 4:271–283, 1991.
- [4] F. Bonnans, E. Ottenwaelter, and H. Zidani. A fast algorithm for the two dimensional HJB equation of stochastic control. *Math. Model. Numer. Anal.*, 38:723–735, 2004.
- [5] F. Bonnans and H. Zidani. Consistency of generalized finite difference schemes for the stochastic HJB equation. *SIAM J. Numer. Anal.*, 41:1008–1021, 2003.
- [6] B. Bouchard and N. Touzi. Discrete-time approximation and Monte Carlo simulation of backward stochastic differential equations. *Stochastic Process. Appl.*, 111:175–206, 2004.
- [7] F. Camilli and M. Falcone. An approximation scheme for the optimal control of diffusion processes. *Math. Model. Numer. Anal.*, 29:97–122, 1995.
- [8] E. Carlini, M. Falcone, and R. Ferretti. An efficient algorithm for Hamilton-Jacobi equations in high dimension. *Comput. Visual. Sci.*, 7:15–29, 2004.
- [9] K. Debrabant and E. R. Jakobsen. Semi-Lagrangian schemes for linear and fully non-linear diffusion equations. *Math. Comp.*, 82:1433–1462, 2013.
- [10] A. Fahim, N. Touzi, and X. Warin. A probabilistic numerical method for fully nonlinear parabolic PDEs. *Ann. Appl. Probab.*, 21:1322–1364, 2011.

- [11] W. H. Fleming and H. M. Soner. *Controlled Markov processes and viscosity solutions*. Springer-Verlag, New York, 2nd edition, 2006.
- [12] S. Graf and H. Luschgy. *Foundation of quantization for probability distributions*. Springer-Verlag, Berlin, 2000.
- [13] L. Györfi, M. Kohler, A. Krzyzak, and H. Walk. *A distribution-free theory of nonparametric regression*. Springer-Verlag, New York, 2002.
- [14] H. Kaise and W. M. McEneaney. Idempotent expansions for continuous-time stochastic control. In *Proc. 49th IEEE Conf. on Decision and Control*, 2010.
- [15] R. V. Kohn and S. Serfaty. A deterministic-control-based approach to fully nonlinear parabolic and elliptic equations. *Comm. Pure Appl. Math.*, 63:1298–1350, 2010.
- [16] N. V. Krylov. *Controlled diffusion processes*. Springer-Verlag, New York, 1980.
- [17] N. V. Krylov. Approximating value functions for controlled degenerate diffusion processes by using piece-wise constant policies. *Electron. J. Probab.*, 4:1–19, 1999.
- [18] H. J. Kushner and P. Dupuis. *Numerical methods for stochastic control problems in continuous time*. Springer-Verlag, New York, 2001.
- [19] J.-P. Lemor, E. Gobet, and X. Warin. Rate of convergence of an empirical regression method for solving generalized backward stochastic differential equations. *Bernoulli*, 12:889–916, 2006.
- [20] F. A. Longstaff and E. S. Schwartz. Valuing american options by simulation: a simple least-squares approach. *Rev. Finan. Stud.*, 14:113–147, 2001.
- [21] G. Pagès, H. Pham, and J. Printems. An optimal Markovian quantization algorithm for multidimensional stochastic control problems. *Stoch. Dyn.*, 4:501–545, 2004.
- [22] G. Pagès and J. Printems. Optimal quadratic quantization for numerics: the Gaussian case. *Monte Carlo Methods Appl.*, 9:135–168, 2003.
- [23] H. Pham. *Continuous-time stochastic control and optimization with financial applications*. Springer, Berlin, 2009.