

Ergodic Processes

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1 Ergodic Processes

Note: In this class, as in many scientific communities, we define ergodicity of a process in the context of a stationary process.

Definition 1. A finite-alphabet stationary process \mathbf{X} is ergodic if $\forall k$ and every $f : \mathcal{X}^{2k+1} \rightarrow \mathbb{R}$,

$$\lim_{n \rightarrow \infty} \frac{1}{n} \sum_{i=1}^n f(X_{i-k}^{i+k}) \rightarrow \mathbb{E}f(X_{-k}^k) \quad w.p.1$$

Intuitively, ergodic processes are “reliable” in that one process realization (L.H.S. of above equation) reveals all process statistics (R.H.S. of above equation).

Exercise 1. Ergodic Examples [1, 2, 3]

(a) Show X_i i.i.d. $\Rightarrow \mathbf{X}$ is ergodic

(b) Show that $\mathbf{X} = \left\{ \begin{array}{ll} \dots 000000000 \dots & w.p. \frac{1}{2} \\ \dots 111111111 \dots & w.p. \frac{1}{2} \end{array} \right\}$ is not ergodic

(c) Show that $\mathbf{X} = \left\{ \begin{array}{ll} \dots 010101010 \dots & w.p. \frac{1}{2} \\ \dots 101010101 \dots & w.p. \frac{1}{2} \end{array} \right\}$ is ergodic

Theorem 2. (The “Ergodic Decomposition” Theorem) Every stationary process is a mixture of ergodic processes. That is, $\forall \mathbf{P}$ stationary, \exists a family of ergodic processes $\{\mathbf{P}_\theta\}_{\theta \in \Theta}$ and a probability measure $\mu(\theta)$ on Θ such that $\mathbf{P} = \int_{\Theta} \mathbf{P}_\theta d\mu(\theta)$.

Conversely, if \mathbf{P} is not ergodic, then it can be expressed as a non-trivial mixture of different stationary processes.

For \mathbf{X} , let $\mathbf{X}^{(k)}$ denote the k -th order super source (e.g. $X_1^{(k)} = X_1^k$, $X_2^{(k)} = X_{k+1}^{2k}$)

Definition 3. \mathbf{X} is “totally ergodic” if $\mathbf{X}^{(k)}$ is ergodic $\forall k$

Example 1 Look at $\mathbf{X} = \left\{ \begin{array}{ll} \dots 01010101 \dots & w.p. \frac{1}{2} \\ \dots 10101010 \dots & w.p. \frac{1}{2} \end{array} \right\}$ and consider $\mathbf{X}^{(2)} = \left\{ \begin{array}{ll} \dots (01)(01)(01)(01) \dots & w.p. \frac{1}{2} \\ \dots (10)(10)(10)(10) \dots & w.p. \frac{1}{2} \end{array} \right\}$.

$\mathbf{X}^{(2)}$ is not ergodic as it is equivalent to the single-letter process $\mathbf{Y} = \left\{ \begin{array}{ll} \dots 00000000 \dots & w.p. \frac{1}{2} \\ \dots 11111111 \dots & w.p. \frac{1}{2} \end{array} \right\}$, which is not ergodic. Thus, \mathbf{X} is not totally ergodic.

Exercise 2. Let \mathbf{X} be a “B-process” defined as $X_i = f(Y_{i-k}^{i+k})$ for i.i.d. process \mathbf{Y} . Show that \mathbf{X} is totally ergodic.

2 Ergodicity: General Setup

We consider a more general setup for ergodicity on the probability space $(\Omega, \mathfrak{F}, \Pr)$. A mapping $\varphi : \Omega \rightarrow \Omega$ is *measure-preserving* if $\Pr(\varphi(A)) = \Pr(A)$ for all $A \in \mathcal{F}$. A random variable $X = X(\omega)$ is a measurable mapping from Ω to \mathbb{R} . An event $A \in \mathcal{F}$ is said to be *invariant* if $\Pr(\varphi^{-1}(A) \Delta A) = 0$, where the notation $A \Delta B = (A \setminus B) \cup (B \setminus A)$ is the symmetric difference of sets A and B .

Exercise 3. Show that the class of invariant events \mathcal{I} is a σ -field.

Definition 4. The mapping φ is “ergodic” if \mathcal{I} is trivial, that is, $\Pr(A) \in \{0, 1\}$ for all $A \in \mathcal{I}$.

Theorem 5 (The ergodic theorem/Birkhoff’s ergodic theorem/Pointwise ergodic theorem [4]). For any $X \in L_1$,

$$\frac{1}{n} \sum_{m=0}^{n-1} X(\varphi^m \omega) \xrightarrow{n \rightarrow \infty} \mathbb{E}[X|\mathcal{I}] \text{ a.s. and in } L_1.$$

Since $\mathbb{E}[X|\mathcal{F}] = \mathbb{E}[X]$ a.s. for all X if and only if \mathcal{F} is trivial, by the ergodic theorem, the following statements are equivalent.

- (a) For any $X \in L_1$, $(1/n) \sum_{m=0}^{n-1} X(\varphi^m \omega) \xrightarrow{n \rightarrow \infty} \mathbb{E}[X]$ w.p.1 and in L_1 .
- (b) \mathcal{I} is trivial.
- (c) φ is ergodic.

To define ergodicity for random processes, we consider the probability space $(\Omega, \mathcal{F}, \Pr)$, where $\Omega = \mathcal{X}^\infty$, the probability measure \Pr is the distribution of the stationary random process, and $\varphi : \Omega \rightarrow \Omega$ is defined as a shift in time, namely $\varphi(\omega)_i = \omega_{i+1}$. Note that the stationarity of the process implies that φ is measure preserving. Then, the above equivalence justifies the following definition of ergodicity for process:

Definition 6. A stationary process \mathbf{X} is “ergodic” if for all k and every $f : \mathcal{X}^{2k+1} \rightarrow \mathbb{R}_X$ s.t. $f(X_{-k}^k) \in L_1$:

$$\frac{1}{n} \sum_{i=1}^n f(X_{i-k}^{i+k}) \xrightarrow{n \rightarrow \infty} \mathbb{E}[f(X_{-k}^k)], \text{ w.p.1 and in } L_1.$$

Exercise 4. For the examples given in Exercise 1, verify ergodicity or lack thereof using Definition 4.

Definition 4 brings some insight into the ergodic decomposition theorem which states that a process \mathbf{X} is ergodic if and only if it cannot be represented as a mixture of different stationary processes. By definition, if \mathbf{X} is not ergodic then \mathcal{I} defined by φ is not trivial. It follows that there exists an event A such that $\Pr(A) > 0$, $\Pr(A^c) > 0$, $\varphi(A) = A$, and $\varphi(A^c) = A^c$. Essentially, we can divide the sample space Ω into A and A^c , and interpret the random process \mathcal{X} as a mixture of two processes in each subset with probability $\Pr(A)$ and $\Pr(A^c)$. For details we refer to Chapter 6 of [4].

The examples of ergodic processes we looked at have infinite memory. Although there are multiple ways to formally define decaying memory, when a process is “mixing” or has decaying memory, even the weakest definition of a “mixing” process implies ergodicity.

References

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- [2] K. Petersen, “Ergodic theory”, Cambridge University Press, 1983
- [3] R. M. Gray, “Entropy and Information Theory”, Springer-Verlag, 1990
- [4] R. Durrett, *Probability: Theory and Examples*, 3rd ed., Duxbury Press,