

Baysian Congestion Control Over a Markovian Network Bandwidth Process

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Introduction

- The rate changes as a stochastic sequence, $B(t)$
- The states $i = 1, \dots, M$
- Transition matrix, P
- Partially Observable Markov Decision Process
- Finite horizon T , time steps $t = 1, \dots, T$
- Our belief vector at time t , $b_t = [b_t(1), \dots, b_t(M)]$

$$b_t(i) = \Pr(B(t) = i), i = 1, \dots, M$$

- Choose an action (rate), a , if higher than $B(t)$, we will find out the exact amount of $B(t)$.

- Immediate reward :

$$R(B(t); a) = \begin{cases} a, & \text{if } a \leq B(t) \\ B(t) - C(a - B(t)), & \text{if } a > B(t) \end{cases}$$

Optimal Policy

Our goal is to find the optimal policy or prove that it has a threshold structure.

$$a_t^{Optimal} = \arg \max_{a=1, \dots, M} V_t(b_t; a)$$

Bounds on Optimal Action

Lower bound: ignoring the impact of the current action on the future reward, myopic policy is given by

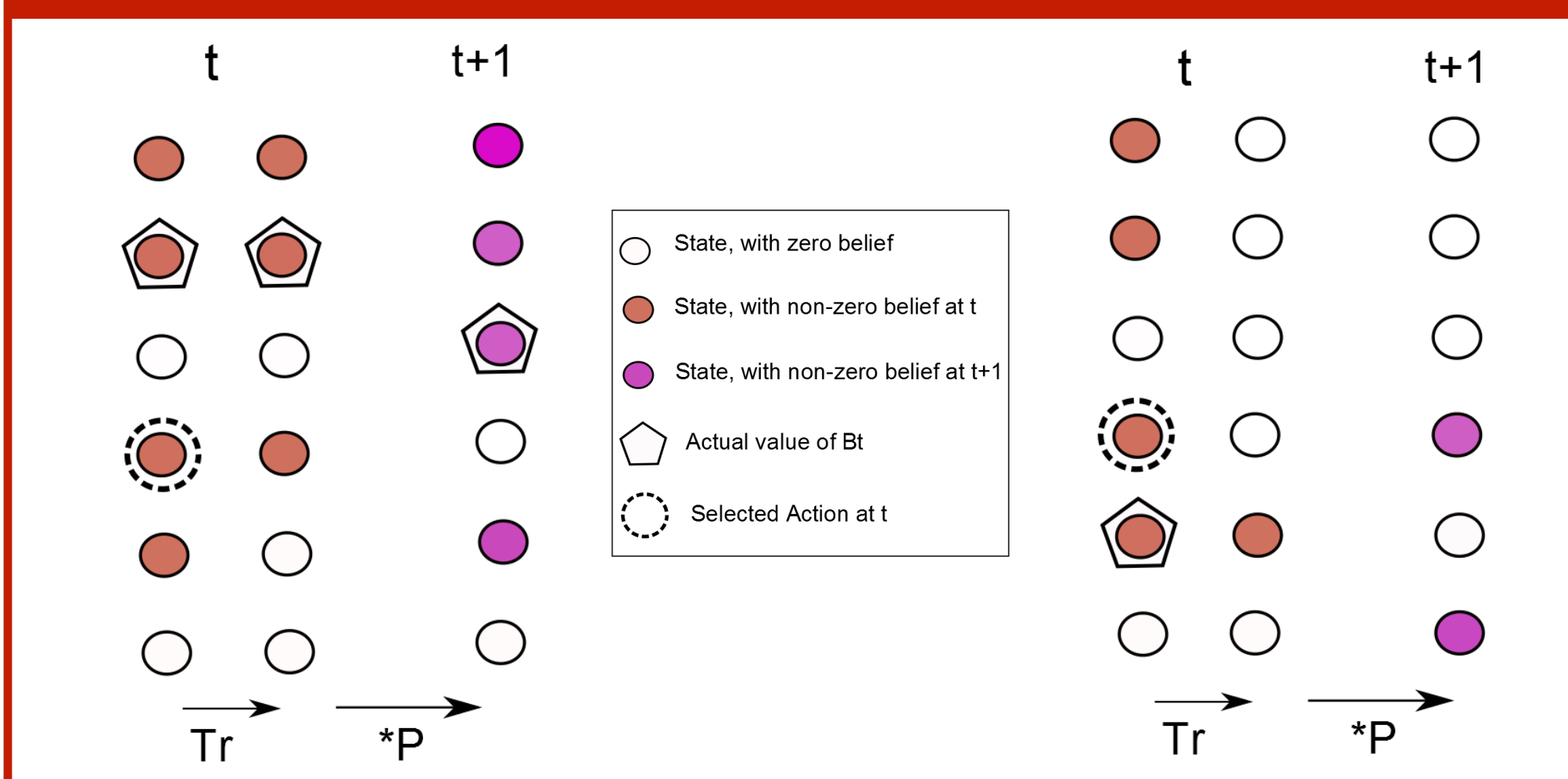
$$a_t^{Myopic}(b_t) = \arg \max_{a=1, \dots, M} \bar{R}(b_t; a) = \min \left\{ a \mid \sum_{i=1}^a b_t(i) \geq \frac{1}{1+C} \right\}$$

- Upper bound:

$$a_t^{UB}(b_t) = \min \left\{ a : \sum_{i=a+1}^M \left[\frac{\beta}{1-\beta} (i-a) + 1 + C \right] b_t(i) \leq C \right\}$$

- Assumption: The P matrix satisfies the State-Independent State Change (SISC) property.

Evolution of belief vector



Problem Formulation

- Policy vector: $\pi = [\pi(1), \dots, \pi(T)]$
- Selecting an action $\pi(t) = a_t \in \{1, \dots, M\}$
- Maximizing total discounted expected reward:

$$\max_{\pi} E^{\pi} \left[\sum_{t=1}^T \beta^{t-1} R(b_t; a_t) \mid b_1 \right]$$

- defining value function, i.e. maximum expected remaining reward starting from time t : $V_t(b)$

Dynamic Programming

$$V_t(b_t) = \max_{a=1, \dots, M} V_t(b_t; a), \quad \forall t = 1, \dots, T$$

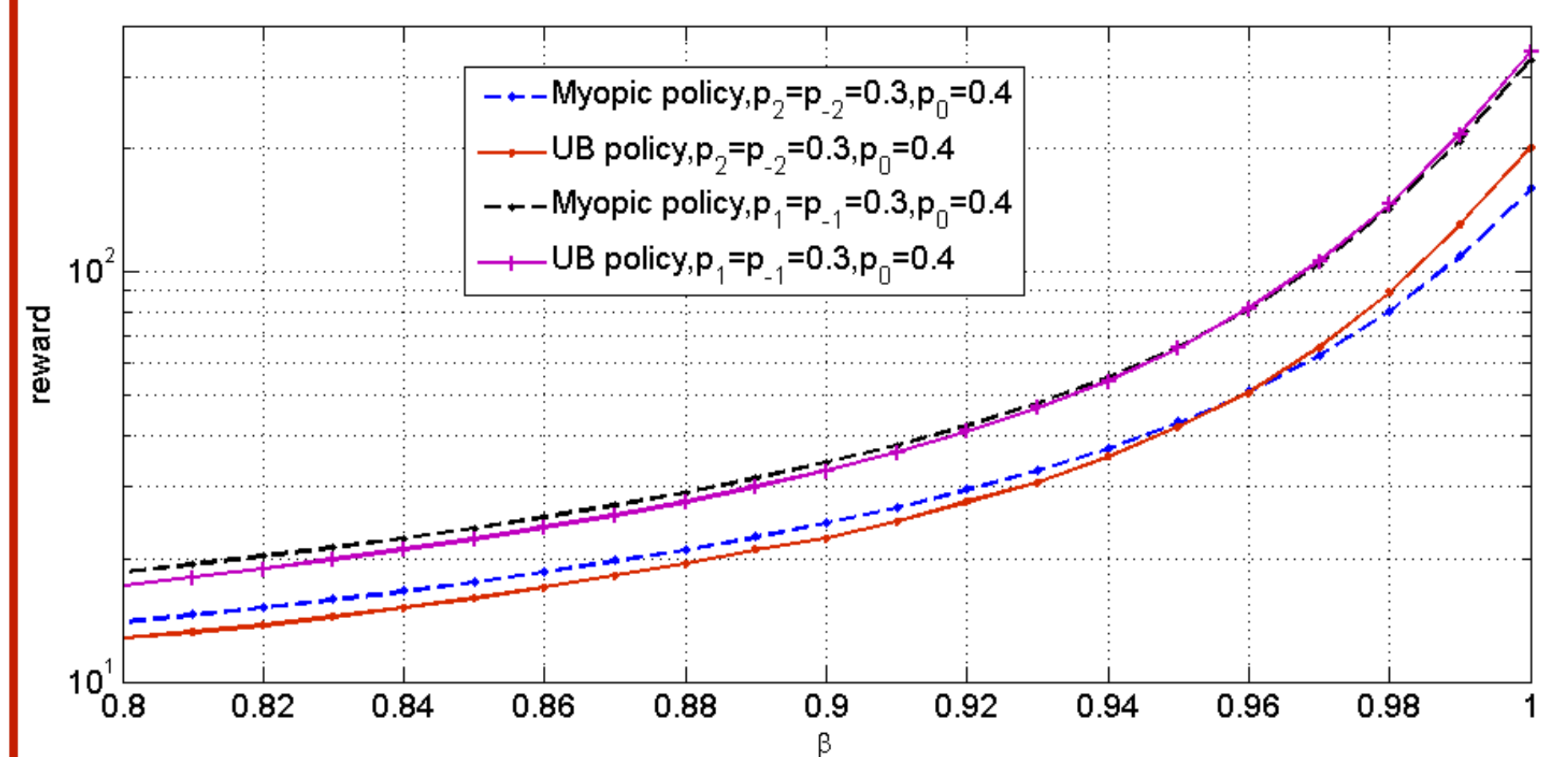
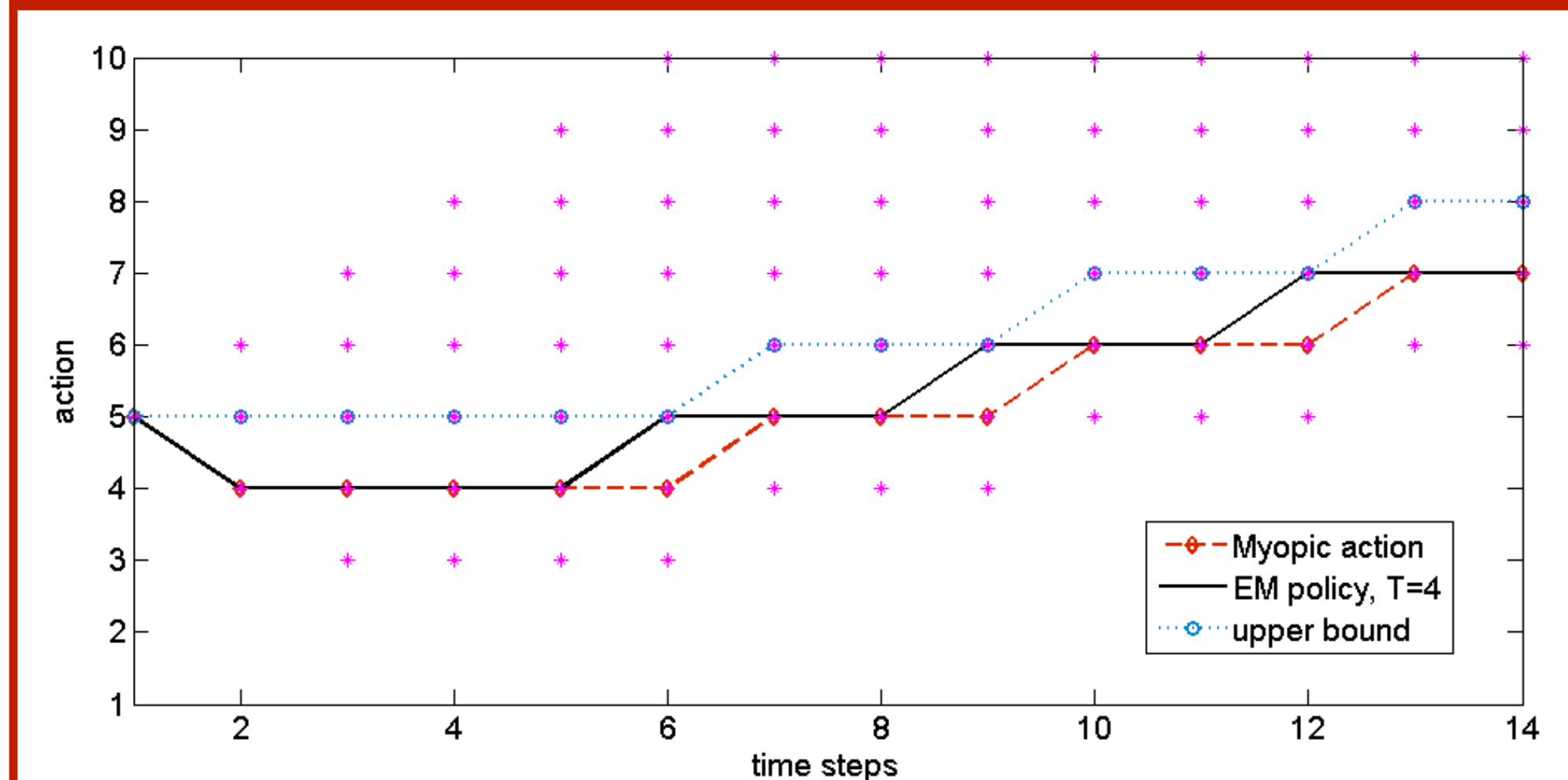
$$V_T(b_T; a) = \bar{R}(b_T; a),$$

$$V_t(b_t; a) = \bar{R}(b_t; a) + \beta V_t^f(b_t; a)$$

$$V_t^f(b_t; a) = E\{V_{t+1}(b_{t+1}) \mid a\}$$

$$= \sum_{i=a}^M b_t(i) V_{t+1}(T_a b_t P) + \sum_{i=1}^{a-1} b_t(i) V_{t+1}(I_i P)$$

Simulation Results



Heuristic: Periodic Myopic-UB policy (some steps myopic and one step UB),

Length of period increase by C and decrease by β

