

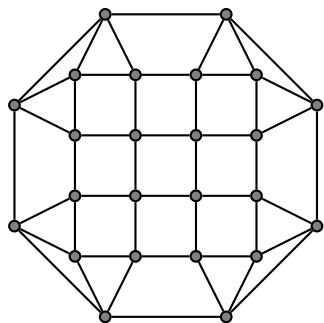
Correlation bounds and one-ended tail triviality for factors of IID on trees

Viktor Harangi

joint work with Ágnes Backhausz, Balázs Gerencsér, and Máté Vizer

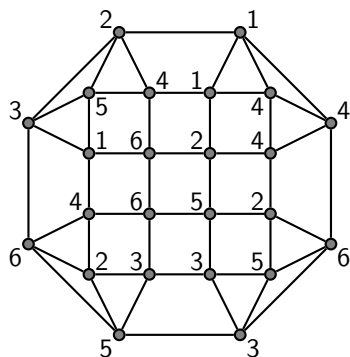
21st April 2016

Motivation: randomized local algorithms on graphs



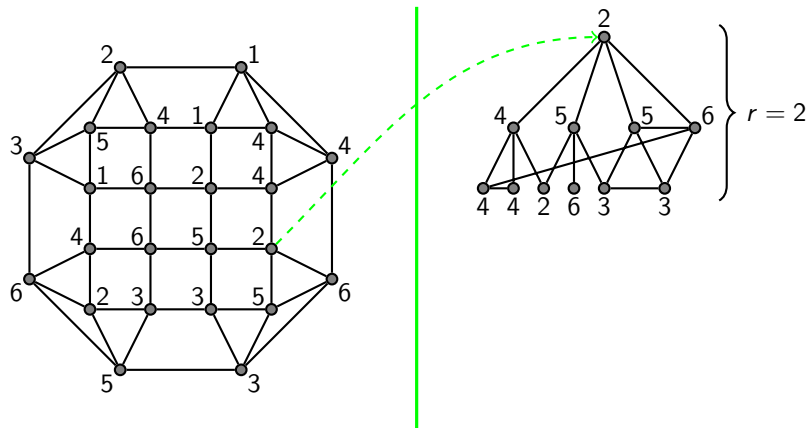
Given a graph,

Motivation: randomized local algorithms on graphs



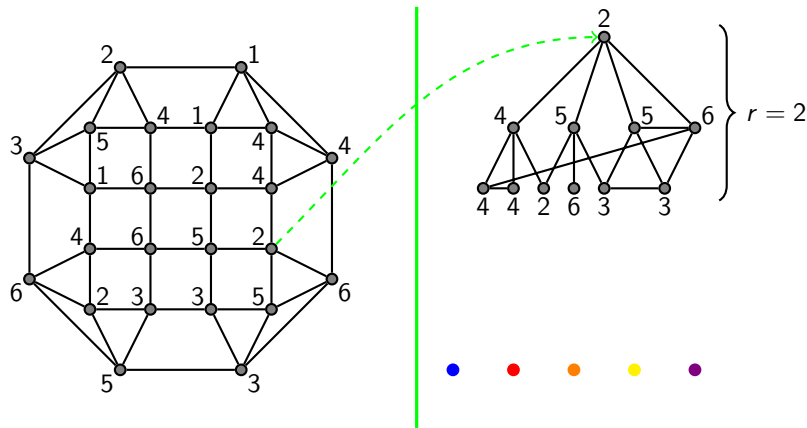
Given a graph, we first put IID labels on its vertices,

Motivation: randomized local algorithms on graphs



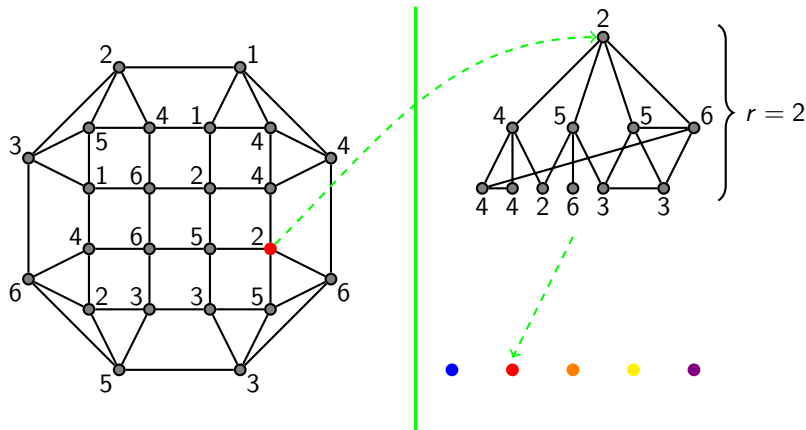
Given a graph, we first put IID labels on its vertices, then apply a fixed *local rule* at each vertex.

Motivation: randomized local algorithms on graphs



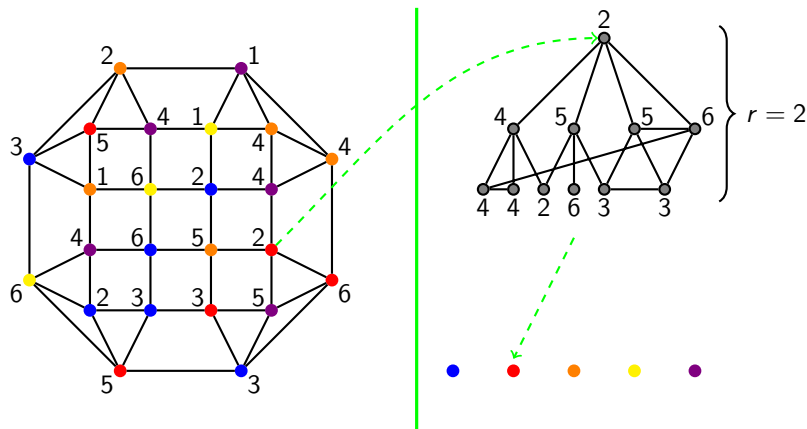
Given a graph, we first put IID labels on its vertices, then apply a fixed *local rule* at each vertex.

Motivation: randomized local algorithms on graphs



Given a graph, we first put IID labels on its vertices, then apply a fixed *local rule* at each vertex. The rule depends on the isomorphism type of the rooted, labelled neighborhood.

Motivation: randomized local algorithms on graphs



Given a graph, we first put IID labels on its vertices, then apply a fixed *local rule* at each vertex. The rule depends on the isomorphism type of the rooted, labelled neighborhood.

An example

Let G be a 3-regular graph with $\text{girth}(G) \geq 5$.

An example

Let G be a 3-regular graph with $\text{girth}(G) \geq 5$.

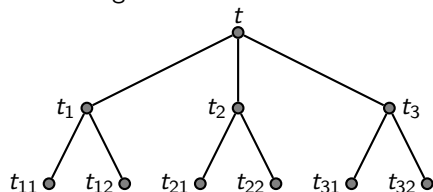
Let us put IID labels of **standard normal distribution** on the vertices.

An example

Let G be a 3-regular graph with $\text{girth}(G) \geq 5$.

Let us put IID labels of **standard normal distribution** on the vertices.

The 2-neighborhood of each vertex looks like this:

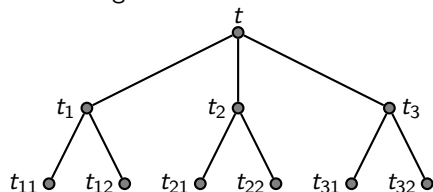


An example

Let G be a 3-regular graph with $\text{girth}(G) \geq 5$.

Let us put IID labels of **standard normal distribution** on the vertices.

The 2-neighborhood of each vertex looks like this:



Apply the following local rule

- **red** if all three inequalities below are satisfied:

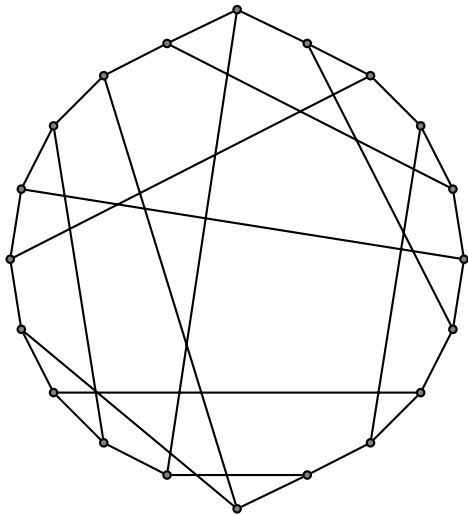
$$t - t_1 - t_2 - t_3 > t_1 - t - t_{11} - t_{12} \text{ and}$$

$$t - t_1 - t_2 - t_3 > t_2 - t - t_{21} - t_{22} \text{ and}$$

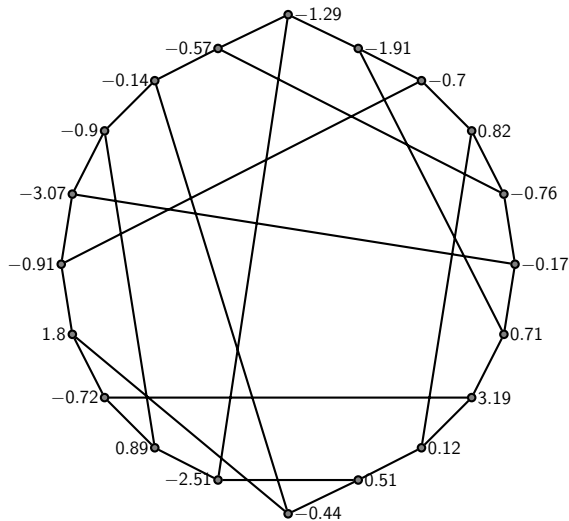
$$t - t_1 - t_2 - t_3 > t_3 - t - t_{31} - t_{32};$$

- **black**, otherwise.

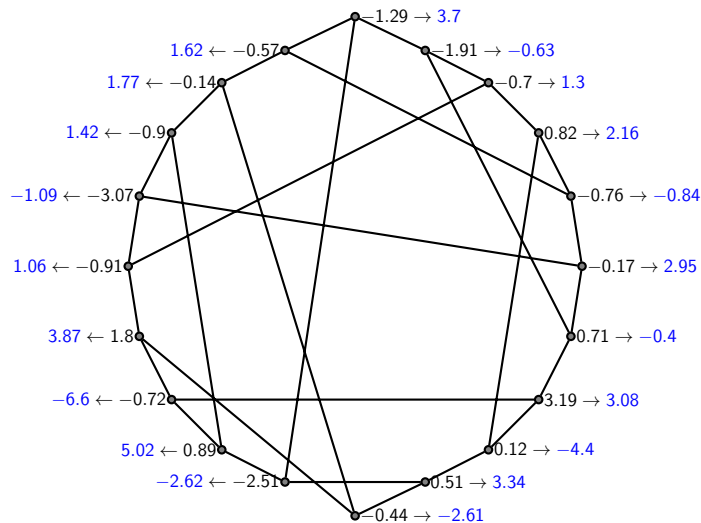
Let's see what happens



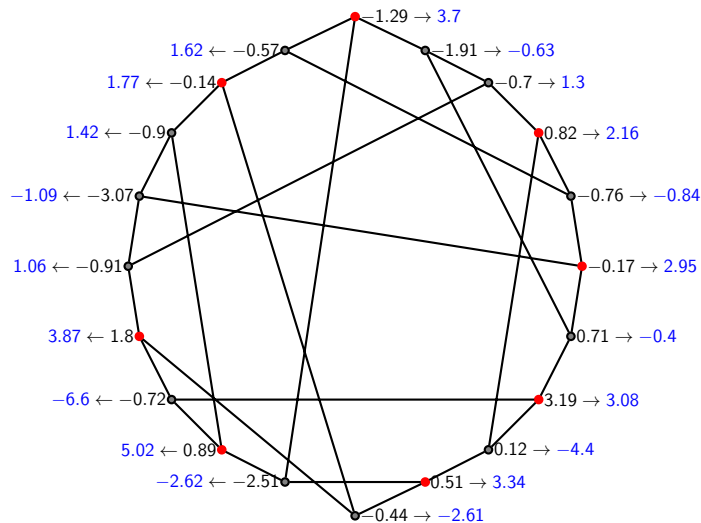
Let's see what happens



Let's see what happens



Let's see what happens



What we gained

We obtained a random independent set on G .

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

Therefore the expected size of our independent set is $\approx 0.327 \cdot |V(G)|$.

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

Therefore the expected size of our independent set is $\approx 0.327 \cdot |V(G)|$.

which proves that

Any 3-regular graph of girth at least 5 has independence ratio at least 0.327.

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

Therefore the expected size of our independent set is $\approx 0.327 \cdot |V(G)|$.

which proves that

Any 3-regular graph of girth at least 5 has independence ratio at least 0.327.

If we consider larger r and more complicated rules, then in the limit we get:

Theorem(Csóka, Gerencsér, H, Virág)

Any 3-regular graph of sufficiently large girth has independence ratio at least 0.43.

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

Therefore the expected size of our independent set is $\approx 0.327 \cdot |V(G)|$.

which proves that

Any 3-regular graph of girth at least 5 has independence ratio at least 0.327.

If we consider larger r and more complicated rules, then in the limit we get:

Theorem(Csóka, Gerencsér, H, Virág)

Any 3-regular graph of sufficiently large girth has independence ratio at least 0.43.
(This is the best bound proved without using computers.)

What we gained

We obtained a random independent set on G .

The probability that a vertex is colored red can be computed easily:

$$\frac{1}{2} - \frac{3}{4\pi} \arccos\left(\frac{3}{4}\right) = 0.327\dots$$

(the area of a certain spherical triangle).

Therefore the expected size of our independent set is $\approx 0.327 \cdot |V(G)|$.

which proves that

Any 3-regular graph of girth at least 5 has independence ratio at least 0.327.

If we consider larger r and more complicated rules, then in the limit we get:

Theorem(Csóka, Gerencsér, H, Virág)

Any 3-regular graph of sufficiently large girth has independence ratio at least 0.43.
(This is the best bound proved without using computers.)

For this one needs to study processes on the limit graph...

Processes on the d -regular tree T_d

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);
- take a measurable function $f: [0, 1]^{V(T_d)} \rightarrow M$ that is invariant under the stabilizer of a root o ;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);
- take a measurable function $f: [0, 1]^{V(T_d)} \rightarrow M$ that is invariant under the stabilizer of a root o ;
- $X_o := f(Z)$ will be the new *label/color* of o ;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);
- take a measurable function $f: [0, 1]^{V(T_d)} \rightarrow M$ that is invariant under the stabilizer of a root o ;
- $X_o := f(Z)$ will be the new *label/color* of o ;
- “move the root” to other vertices and apply the same rule: we get the factor of IID process $X = (X_v)_{v \in V(T_d)}$ on $M^{V(T_d)}$;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);
- take a measurable function $f: [0, 1]^{V(T_d)} \rightarrow M$ that is invariant under the stabilizer of a root o ;
- $X_o := f(Z)$ will be the new *label/color* of o ;
- “move the root” to other vertices and apply the same rule: we get the factor of IID process $X = (X_v)_{v \in V(T_d)}$ on $M^{V(T_d)}$;
- the joint distribution of X is clearly invariant under $\text{Aut}(T_d)$;

Processes on the d -regular tree T_d

- T_d : an infinite tree where each vertex has d neighbors ($d \geq 3$);
- $V(T_d)$: vertex-set; $\Gamma = \text{Aut}(T_d)$: the group of graph automorphisms of T_d ;
- $\text{Aut}(T_d)$ acts on $M^{V(T_d)}$ in a natural way for any set M ;
- *stabilizer* of a fixed vertex o : group of those automorphisms that fix o .

Factor of IID processes

- take an IID process $Z = (Z_v)_{v \in V(T_d)}$ on $[0, 1]^{V(T_d)}$;
- take a measurable space M (usually \mathbb{R} or a discrete set of colors);
- take a measurable function $f: [0, 1]^{V(T_d)} \rightarrow M$ that is invariant under the stabilizer of a root o ;
- $X_o := f(Z)$ will be the new *label/color* of o ;
- “move the root” to other vertices and apply the same rule: we get the factor of IID process $X = (X_v)_{v \in V(T_d)}$ on $M^{V(T_d)}$;
- the joint distribution of X is clearly invariant under $\text{Aut}(T_d)$;
- X is said to be a *block factor* if f depends on a finite neighborhood of o .

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .
- **Generalized Bernoulli shifts:** $\Gamma \curvearrowright (K^S, \kappa^S)$, where S is a countable set with a Γ -action.

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .
- **Generalized Bernoulli shifts:** $\Gamma \curvearrowright (K^S, \kappa^S)$, where S is a countable set with a Γ -action.
- **Invariant measures:** given a fixed measurable action $\Gamma \curvearrowright \Omega$, one might be interested in the measures μ on Ω that are invariant under the Γ -action.

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .
- **Generalized Bernoulli shifts:** $\Gamma \curvearrowright (K^S, \kappa^S)$, where S is a countable set with a Γ -action.
- **Invariant measures:** given a fixed measurable action $\Gamma \curvearrowright \Omega$, one might be interested in the measures μ on Ω that are invariant under the Γ -action.
- **Ergodic processes:** the extremal Γ -invariant measures.

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .
- **Generalized Bernoulli shifts:** $\Gamma \curvearrowright (K^S, \kappa^S)$, where S is a countable set with a Γ -action.
- **Invariant measures:** given a fixed measurable action $\Gamma \curvearrowright \Omega$, one might be interested in the measures μ on Ω that are invariant under the Γ -action.
- **Ergodic processes:** the extremal Γ -invariant measures.
- **Factors of Bernoulli shifts:** $F: K_1^{S_1} \rightarrow K_2^{S_2}$ is a factor map if it commutes with the Γ -actions. If $\nu = \kappa_1^{S_1}$, then the push-forward measure $\mu = F_*\nu$ is also Γ -invariant.

Dynamical systems over groups

- **Dynamical system:** a group Γ acting on a probability space (Ω, μ) by measure-preserving transformations.
- **Bernoulli shifts:** the natural action on $(\Omega, \mu) = (K^\Gamma, \kappa^\Gamma)$ for some probability space (K, κ) .
- **Generalized Bernoulli shifts:** $\Gamma \curvearrowright (K^S, \kappa^S)$, where S is a countable set with a Γ -action.
- **Invariant measures:** given a fixed measurable action $\Gamma \curvearrowright \Omega$, one might be interested in the measures μ on Ω that are invariant under the Γ -action.
- **Ergodic processes:** the extremal Γ -invariant measures.
- **Factors of Bernoulli shifts:** $F: K_1^{S_1} \rightarrow K_2^{S_2}$ is a factor map if it commutes with the Γ -actions. If $\nu = \kappa_1^{S_1}$, then the push-forward measure $\mu = F_*\nu$ is also Γ -invariant.

The special considered in this talk

$\Gamma = \text{Aut}(T_d)$ and $S = V(T_d)$.

Tail σ -algebras

Let $\Omega = M^{V(T_d)}$ and for $v \in V(T_d)$ let $\pi_v: M^{V(T_d)} \rightarrow M$ denote the natural coordinate projection. For $V \subseteq V(T_d)$ let $\sigma(V)$ be the σ -algebra generated by the maps π_v , $v \in V$.

Tail

The *tail σ -algebra* is defined as $\bigcap_r \sigma(V(T_d) \setminus B_r)$, where B_r stands for the r -ball around some fixed vertex o . (Clearly, the tail does not depend on the choice of o .)

Tail σ -algebras

Let $\Omega = M^{V(T_d)}$ and for $v \in V(T_d)$ let $\pi_v: M^{V(T_d)} \rightarrow M$ denote the natural coordinate projection. For $V \subseteq V(T_d)$ let $\sigma(V)$ be the σ -algebra generated by the maps $\pi_v, v \in V$.

Tail

The *tail σ -algebra* is defined as $\bigcap_r \sigma(V(T_d) \setminus B_r)$, where B_r stands for the r -ball around some fixed vertex o . (Clearly, the tail does not depend on the choice of o .)

1-ended tails

The *1-ended tail σ -algebra* corresponding to an infinite simple path (v_0, v_1, v_2, \dots) is $\bigcap_n \sigma(D_n)$, where D_n is the set of vertices closer to v_n than to v_{n-1} .

Tail σ -algebras

Let $\Omega = M^{V(T_d)}$ and for $v \in V(T_d)$ let $\pi_v: M^{V(T_d)} \rightarrow M$ denote the natural coordinate projection. For $V \subseteq V(T_d)$ let $\sigma(V)$ be the σ -algebra generated by the maps $\pi_v, v \in V$.

Tail

The *tail σ -algebra* is defined as $\bigcap_r \sigma(V(T_d) \setminus B_r)$, where B_r stands for the r -ball around some fixed vertex o . (Clearly, the tail does not depend on the choice of o .)

1-ended tails

The *1-ended tail σ -algebra* corresponding to an infinite simple path (v_0, v_1, v_2, \dots) is $\bigcap_n \sigma(D_n)$, where D_n is the set of vertices closer to v_n than to v_{n-1} .

A σ -algebra is said to be *trivial* w.r.t. a probability measure if it contains only sets of measure 0 or 1.

It is easy to see that for an $\text{Aut}(T_d)$ -invariant measure μ on $M^{V(T_d)}$ the 1-ended tails are all trivial or none are trivial.

Some simple results and open questions

Some simple results and open questions

- Open: trivial tail implies FIID?

Some simple results and open questions

- Open: trivial tail implies FIID?
- It follows easily from the Kolmogorov 0-1 Law: block factors have trivial tail.

Some simple results and open questions

- Open: trivial tail implies FIID?
- It follows easily from the Kolmogorov 0-1 Law: block factors have trivial tail.
- Not true for arbitrary factors!

Some simple results and open questions

- Open: trivial tail implies FIID?
- It follows easily from the Kolmogorov 0-1 Law: block factors have trivial tail.
- Not true for arbitrary factors!
- In fact, there exists a FIID for which “any tail broader than a 1-ended tail” is non-trivial.

Some simple results and open questions

- Open: trivial tail implies FIID?
- It follows easily from the Kolmogorov 0-1 Law: block factors have trivial tail.
- Not true for arbitrary factors!
- In fact, there exists a FIID for which “any tail broader than a 1-ended tail” is non-trivial.
- Szegedy’s “sparse tail” for discrete M ?

Ergodic processes

Definition

Let $\Gamma \curvearrowright (\Omega, \mu)$ be a dynamical system over Γ .

It is said to be *ergodic* (or Γ -*ergodic*) if for any measurable, Γ -invariant $A \subset \Omega$ it holds that $\mu(A) = 0$ or $\mu(A) = 1$.

That is, any measurable, Γ -invariant $\Omega \rightarrow \mathbb{R}$ function is μ -a.e. constant.

Ergodic processes

Definition

Let $\Gamma \curvearrowright (\Omega, \mu)$ be a dynamical system over Γ .

It is said to be *ergodic* (or Γ -*ergodic*) if for any measurable, Γ -invariant $A \subset \Omega$ it holds that $\mu(A) = 0$ or $\mu(A) = 1$.

That is, any measurable, Γ -invariant $\Omega \rightarrow \mathbb{R}$ function is μ -a.e. constant.

Question: Does $\text{Aut}(T_d)$ -ergodicity imply 1-ended tail triviality?

Ergodic processes

Definition

Let $\Gamma \curvearrowright (\Omega, \mu)$ be a dynamical system over Γ .

It is said to be *ergodic* (or Γ -*ergodic*) if for any measurable, Γ -invariant $A \subset \Omega$ it holds that $\mu(A) = 0$ or $\mu(A) = 1$.

That is, any measurable, Γ -invariant $\Omega \rightarrow \mathbb{R}$ function is μ -a.e. constant.

Question: Does $\text{Aut}(T_d)$ -ergodicity imply 1-ended tail triviality? **Not quite!**

Let $V(T_d) = V_0 \cup V_1$ be the partition of $V(T_d)$ into *even and odd vertices*, and consider the process that is $\mathbb{1}_{V_0}$ with probability $1/2$ and $\mathbb{1}_{V_1}$ also with probability $1/2$.

Ergodic processes

Definition

Let $\Gamma \curvearrowright (\Omega, \mu)$ be a dynamical system over Γ .

It is said to be *ergodic* (or Γ -*ergodic*) if for any measurable, Γ -invariant $A \subset \Omega$ it holds that $\mu(A) = 0$ or $\mu(A) = 1$.

That is, any measurable, Γ -invariant $\Omega \rightarrow \mathbb{R}$ function is μ -a.e. constant.

Question: Does $\text{Aut}(T_d)$ -ergodicity imply 1-ended tail triviality? **Not quite!**

Let $V(T_d) = V_0 \cup V_1$ be the partition of $V(T_d)$ into *even and odd vertices*, and consider the process that is $\mathbb{1}_{V_0}$ with probability $1/2$ and $\mathbb{1}_{V_1}$ also with probability $1/2$.

Instead: consider the group $\text{Aut}_+(T_d)$ of *parity-preserving* automorphisms of T_d ; this is a subgroup of $\text{Aut}(T_d)$ of index 2.

Ergodic processes

Definition

Let $\Gamma \curvearrowright (\Omega, \mu)$ be a dynamical system over Γ .

It is said to be *ergodic* (or Γ -*ergodic*) if for any measurable, Γ -invariant $A \subset \Omega$ it holds that $\mu(A) = 0$ or $\mu(A) = 1$.

That is, any measurable, Γ -invariant $\Omega \rightarrow \mathbb{R}$ function is μ -a.e. constant.

Question: Does $\text{Aut}(T_d)$ -ergodicity imply 1-ended tail triviality? **Not quite!**

Let $V(T_d) = V_0 \cup V_1$ be the partition of $V(T_d)$ into *even and odd vertices*, and consider the process that is $\mathbb{1}_{V_0}$ with probability $1/2$ and $\mathbb{1}_{V_1}$ also with probability $1/2$.

Instead: consider the group $\text{Aut}_+(T_d)$ of *parity-preserving* automorphisms of T_d ; this is a subgroup of $\text{Aut}(T_d)$ of index 2.

Any $\text{Aut}(T_d)$ -ergodic process is the *equal mixture* of two $\text{Aut}_+(T_d)$ -ergodic processes.

A result of Pemantle

Theorem(Pemantle, 1992)

Let $\Gamma_+ = \text{Aut}_+(T_d)$ and let μ be an Γ_+ -invariant process on $\Omega = M^V(T_d)$.
If μ is Γ_+ -ergodic, then it is 1-ended tail trivial.

A result of Pemantle

Theorem(Pemantle, 1992)

Let $\Gamma_+ = \text{Aut}_+(T_d)$ and let μ be an Γ_+ -invariant process on $\Omega = M^{V(T_d)}$.
If μ is Γ_+ -ergodic, then it is 1-ended tail trivial.

Proof strategy:

Let B be an event in $\Omega = M^{V(T_d)}$ that depends on finitely many coordinates.

A result of Pemantle

Theorem(Pemantle, 1992)

Let $\Gamma_+ = \text{Aut}_+(T_d)$ and let μ be an Γ_+ -invariant process on $\Omega = M^{V(T_d)}$. If μ is Γ_+ -ergodic, then it is 1-ended tail trivial.

Proof strategy:

Let B be an event in $\Omega = M^{V(T_d)}$ that depends on finitely many coordinates. We need to show that B is independent from $\sigma(\alpha)$ for any end $\alpha \in \partial T_d$. Equivalently:

$$\mathbf{E}_\mu (\mathbb{1}_B | \sigma(\alpha)) \text{ is } \mu\text{-a.e. constant.}$$

A result of Pemantle

Theorem(Pemantle, 1992)

Let $\Gamma_+ = \text{Aut}_+(T_d)$ and let μ be an Γ_+ -invariant process on $\Omega = M^{V(T_d)}$. If μ is Γ_+ -ergodic, then it is 1-ended tail trivial.

Proof strategy:

Let B be an event in $\Omega = M^{V(T_d)}$ that depends on finitely many coordinates. We need to show that B is independent from $\sigma(\alpha)$ for any end $\alpha \in \partial T_d$. Equivalently:

$$\mathbf{E}_\mu(\mathbb{1}_B | \sigma(\alpha)) \text{ is } \mu\text{-a.e. constant.}$$

For the sake of simplicity, we will only consider events that depend only on one coordinate:

$$B = \{\omega : \omega_v \in A\} \text{ for some vertex } v \in V(T_d) \text{ and a measurable set } A \subset M.$$

Definitions

The boundary of T_d

- the boundary ∂T_d is defined as the set of ends in T_d ;
- there is a natural topology (and the corresponding Borel σ -algebra) on T_d ;
- for any vertex $v \in V(T_d)$ a probability measure m_v can be defined on ∂T_d ; essentially the “uniform measure” as seen from v ;
- these measures are absolutely continuous w.r.t. each other, thus null sets on ∂T_d are well defined.

Definitions

The boundary of T_d

- the boundary ∂T_d is defined as the set of ends in T_d ;
- there is a natural topology (and the corresponding Borel σ -algebra) on T_d ;
- for any vertex $v \in V(T_d)$ a probability measure m_v can be defined on ∂T_d ; essentially the “uniform measure” as seen from v ;
- these measures are absolutely continuous w.r.t. each other, thus null sets on ∂T_d are well defined.

Height function in direction α

A height function $h_\alpha: V(T_d) \rightarrow \mathbb{Z}$ can be defined for any end α .

Definitions

The boundary of T_d

- the boundary ∂T_d is defined as the set of ends in T_d ;
- there is a natural topology (and the corresponding Borel σ -algebra) on T_d ;
- for any vertex $v \in V(T_d)$ a probability measure m_v can be defined on ∂T_d ; essentially the “uniform measure” as seen from v ;
- these measures are absolutely continuous w.r.t. each other, thus null sets on ∂T_d are well defined.

Height function in direction α

A height function $h_\alpha: V(T_d) \rightarrow \mathbb{Z}$ can be defined for any end α .

Horocycles

The level sets of h_α are called the *horocycles* in direction α .
The horocycle through v in direction α is denoted by $C_\alpha(v)$.

Sketch of the proof

Easy to see

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

- $g: \Omega \times V(T_d) \times \partial T_d \rightarrow \mathbb{R}$ is a bounded, measurable function;

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

- $g: \Omega \times V(T_d) \times \partial T_d \rightarrow \mathbb{R}$ is a bounded, measurable function;
- for any fixed $\omega \in \Omega$ and $\alpha \in \partial T_d$: $g(\omega, \cdot, \alpha)$ only depends on $h_\alpha(\cdot)$;

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

- $g: \Omega \times V(T_d) \times \partial T_d \rightarrow \mathbb{R}$ is a bounded, measurable function;
- for any fixed $\omega \in \Omega$ and $\alpha \in \partial T_d$: $g(\omega, \cdot, \alpha)$ only depends on $h_\alpha(\cdot)$;
- g is Γ_+ -invariant: $g(\gamma \cdot \omega, \gamma \cdot \nu, \gamma \cdot \alpha) = g(\omega, \nu, \alpha)$ for all $\gamma \in \Gamma_+$.

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

- $g: \Omega \times V(T_d) \times \partial T_d \rightarrow \mathbb{R}$ is a bounded, measurable function;
- for any fixed $\omega \in \Omega$ and $\alpha \in \partial T_d$: $g(\omega, \cdot, \alpha)$ only depends on $h_\alpha(\cdot)$;
- g is Γ_+ -invariant: $g(\gamma \cdot \omega, \gamma \cdot \nu, \gamma \cdot \alpha) = g(\omega, \nu, \alpha)$ for all $\gamma \in \Gamma_+$.

Claim

If μ is Γ_+ -invariant and g satisfies the above properties, then for μ -a.e. ω_0 it holds that $g(\omega_0, \nu, \alpha)$ depends only on the parity of ν (modulo null sets of α).

Sketch of the proof

Easy to see

Fix a measurable $A \subset M$. Then the function

$$g(\omega, \nu, \alpha) = \mathbf{E}_\mu (\mathbb{1}_{\{\omega_\nu \in A\}} | \sigma(\alpha))$$

can be defined in such a way that it satisfies the following properties:

- $g: \Omega \times V(T_d) \times \partial T_d \rightarrow \mathbb{R}$ is a bounded, measurable function;
- for any fixed $\omega \in \Omega$ and $\alpha \in \partial T_d$: $g(\omega, \cdot, \alpha)$ only depends on $h_\alpha(\cdot)$;
- g is Γ_+ -invariant: $g(\gamma \cdot \omega, \gamma \cdot \nu, \gamma \cdot \alpha) = g(\omega, \nu, \alpha)$ for all $\gamma \in \Gamma_+$.

Claim

If μ is Γ_+ -invariant and g satisfies the above properties, then for μ -a.e. ω_0 it holds that $g(\omega_0, \nu, \alpha)$ depends only on the parity of ν (modulo null sets of α).

Γ_+ -ergodicity + Claim \implies Theorem

We get two Γ_+ -invariant functions: $g_{\text{even}}: \Omega \rightarrow \mathbb{R}$ and $g_{\text{odd}}: \Omega \rightarrow \mathbb{R}$. If μ is ergodic, they must be μ -a.e. constant.

Proof of the claim, I

Fix v and let $v_0, v_1, v_2 \dots$ be a non-backtracking random walk started at $v_0 = v$, so the corresponding (random) end α has distribution m_v .

Proof of the claim, I

Fix v and let $v_0, v_1, v_2 \dots$ be a non-backtracking random walk started at $v_0 = v$, so the corresponding (random) end α has distribution m_v .

For any fixed ω

$G(\omega, v, v_k) := \mathbf{E}_{\text{rw}}(g(\omega, v, \alpha) | v_0, v_1, \dots, v_k)$ is a bounded martingale,

and it converges almost surely to $g(\omega, v, \alpha)$ as $k \rightarrow \infty$.

Proof of the claim, I

Fix v and let $v_0, v_1, v_2 \dots$ be a non-backtracking random walk started at $v_0 = v$, so the corresponding (random) end α has distribution m_v .

For any fixed ω

$G(\omega, v, v_k) := \mathbf{E}_{\text{rw}}(g(\omega, v, \alpha) | v_0, v_1, \dots, v_k)$ is a bounded martingale,

and it converges almost surely to $g(\omega, v, \alpha)$ as $k \rightarrow \infty$.

Thus for any fixed ω and $\varepsilon > 0$:

$$\mathbf{P}_{\text{rw}}(|G(\omega, v, v_k) - g(\omega, v, \alpha)| > \varepsilon) \rightarrow 0 \text{ as } k \rightarrow \infty.$$

Proof of the claim, I

Fix v and let $v_0, v_1, v_2 \dots$ be a non-backtracking random walk started at $v_0 = v$, so the corresponding (random) end α has distribution m_v .

For any fixed ω

$G(\omega, v, v_k) := \mathbf{E}_{\text{rw}}(g(\omega, v, \alpha) | v_0, v_1, \dots, v_k)$ is a bounded martingale,

and it converges almost surely to $g(\omega, v, \alpha)$ as $k \rightarrow \infty$.

Thus for any fixed ω and $\varepsilon > 0$:

$$\mathbf{P}_{\text{rw}}(|G(\omega, v, v_k) - g(\omega, v, \alpha)| > \varepsilon) \rightarrow 0 \text{ as } k \rightarrow \infty.$$

Therefore $\exists N(\varepsilon)$ such that for any $k \geq N(\varepsilon)$:

$$\mathbf{P}_{\mu, \text{rw}}(|G(\omega, v, v_k) - g(\omega, v, \alpha)| > \varepsilon) < \varepsilon.$$

Proof of the claim, I

Fix v and let $v_0, v_1, v_2 \dots$ be a non-backtracking random walk started at $v_0 = v$, so the corresponding (random) end α has distribution m_v .

For any fixed ω

$G(\omega, v, v_k) := \mathbf{E}_{\text{rw}}(g(\omega, v, \alpha) | v_0, v_1, \dots, v_k)$ is a bounded martingale,

and it converges almost surely to $g(\omega, v, \alpha)$ as $k \rightarrow \infty$.

Thus for any fixed ω and $\varepsilon > 0$:

$$\mathbf{P}_{\text{rw}}(|G(\omega, v, v_k) - g(\omega, v, \alpha)| > \varepsilon) \rightarrow 0 \text{ as } k \rightarrow \infty.$$

Therefore $\exists N(\varepsilon)$ such that for any $k \geq N(\varepsilon)$:

$$\mathbf{P}_{\mu, \text{rw}}(|G(\omega, v, v_k) - g(\omega, v, \alpha)| > \varepsilon) < \varepsilon.$$

Now we fix $N \geq N(\varepsilon)$ and consider two such random walks v_0, v_1, \dots and u_0, u_1, \dots (with corresponding ends α and β) coupled in a way that $v_k = u_k$ holds if and only if $k \leq N$. Then

$$\begin{aligned} \mathbf{P}_{\mu, \text{rw}}(|g(\omega, v, \alpha) - g(\omega, v, \beta)| > 2\varepsilon) \\ \leq \mathbf{P}_{\mu, \text{rw}}(|G(\omega, v, v_N) - g(\omega, v, \alpha)| > \varepsilon) \\ + \mathbf{P}_{\mu, \text{rw}}(|G(\omega, v, v_N) - g(\omega, v, \beta)| > \varepsilon) < \varepsilon + \varepsilon = 2\varepsilon. \end{aligned}$$

Proof of the claim, II

So we saw that $\mathbf{P}_{\mu, \text{rw}} (|g(\omega, \nu, \alpha) - g(\omega, \nu, \beta)| > 2\varepsilon) < 2\varepsilon,$

where α and β are random ends “branching” after exactly N steps from ν .

Proof of the claim, II

So we saw that $\mathbf{P}_{\mu, \text{rw}} (|g(\omega, \nu, \alpha) - g(\omega, \nu, \beta)| > 2\varepsilon) < 2\varepsilon,$

where α and β are random ends “branching” after exactly N steps from ν . Because of the Γ_+ -invariance of g , the probability

$$\mathbf{P}_{\mu} (|g(\omega, \nu, \alpha_0) - g(\omega, \nu, \beta_0)| > 2\varepsilon)$$

is the same for any instances α_0, β_0 of the random ends.

Proof of the claim, II

So we saw that $\mathbf{P}_{\mu, \text{rw}} (|g(\omega, v, \alpha) - g(\omega, v, \beta)| > 2\varepsilon) < 2\varepsilon,$

where α and β are random ends “branching” after exactly N steps from v . Because of the Γ_+ -invariance of g , the probability

$$\mathbf{P}_{\mu} (|g(\omega, v, \alpha_0) - g(\omega, v, \beta_0)| > 2\varepsilon)$$

is the same for any instances α_0, β_0 of the random ends.

Therefore this probability is less than 2ε .

The horocycles $C_{\alpha_0}(v)$ and $C_{\beta_0}(v)$ have $(d-2)(d-1)^{N-1}$ common vertices.

Proof of the claim, II

So we saw that $\mathbf{P}_{\mu, \text{rw}} (|g(\omega, v, \alpha) - g(\omega, v, \beta)| > 2\varepsilon) < 2\varepsilon$,

where α and β are random ends “branching” after exactly N steps from v . Because of the Γ_+ -invariance of g , the probability

$$\mathbf{P}_{\mu} (|g(\omega, v, \alpha_0) - g(\omega, v, \beta_0)| > 2\varepsilon)$$

is the same for any instances α_0, β_0 of the random ends.

Therefore this probability is less than 2ε .

The horocycles $C_{\alpha_0}(v)$ and $C_{\beta_0}(v)$ have $(d-2)(d-1)^{N-1}$ common vertices.

We essentially obtained that

If we consider g as a $\Omega \times \{\text{horocycles}\} \rightarrow \mathbb{R}$ function, then for horocycles C_1 and C_2 with sufficiently large intersection $g(\omega, C_1)$ and $g(\omega, C_2)$ are arbitrarily likely to be arbitrarily close to each other.

Proof of the claim, II

So we saw that $\mathbf{P}_{\mu, \text{rw}} (|g(\omega, v, \alpha) - g(\omega, v, \beta)| > 2\varepsilon) < 2\varepsilon$,

where α and β are random ends “branching” after exactly N steps from v . Because of the Γ_+ -invariance of g , the probability

$$\mathbf{P}_{\mu} (|g(\omega, v, \alpha_0) - g(\omega, v, \beta_0)| > 2\varepsilon)$$

is the same for any instances α_0, β_0 of the random ends.

Therefore this probability is less than 2ε .

The horocycles $C_{\alpha_0}(v)$ and $C_{\beta_0}(v)$ have $(d-2)(d-1)^{N-1}$ common vertices.

We essentially obtained that

If we consider g as a $\Omega \times \{\text{horocycles}\} \rightarrow \mathbb{R}$ function, then for horocycles C_1 and C_2 with sufficiently large intersection $g(\omega, C_1)$ and $g(\omega, C_2)$ are arbitrarily likely to be arbitrarily close to each other.

However, it is easy to see that for any two horocycles C and C' of the same parity, there is an integer m such that for any N there exists a chain of horocycles $C_0 = C, C_1, \dots, C_m = C'$ with the property that C_{i-1} and C_i share at least $(d-2)(d-1)^{N-1}$ vertices.

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Theorem(Backhausz, Szegedy, Virág)

$$|\text{corr}(X_u, X_v)| \leq \left(k + 1 - \frac{2k}{d}\right) \left(\frac{1}{\sqrt{d-1}}\right)^k, \text{ where } k = \text{dist}(u, v),$$

provided that $\text{var } X_v < \infty$.

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Theorem(Backhausz, Szegedy, Virág)

$$|\text{corr}(X_u, X_v)| \leq \left(k + 1 - \frac{2k}{d}\right) \left(\frac{1}{\sqrt{d-1}}\right)^k, \text{ where } k = \text{dist}(u, v),$$

provided that $\text{var } X_v < \infty$. (This is sharp.)

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Theorem(Backhausz, Szegedy, Virág)

$$|\text{corr}(X_u, X_v)| \leq \left(k + 1 - \frac{2k}{d}\right) \left(\frac{1}{\sqrt{d-1}}\right)^k, \text{ where } k = \text{dist}(u, v),$$

provided that $\text{var } X_v < \infty$. (This is sharp.)

Theorem(Backhausz, Gerencsér, H, Vizer)

If two connected subsets $V_1, V_2 \subset V(T_d)$ have large distance, then they are “almost independent” in the following sense: for an arbitrary factor X , any function f_1 of $(X_v)_{v \in V_1}$ and any function f_2 of $(X_v)_{v \in V_2}$ have small correlation, essentially of (the optimal) order $1/(\sqrt{d-1})^k$.

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Theorem(Backhausz, Szegedy, Virág)

$$|\text{corr}(X_u, X_v)| \leq \left(k + 1 - \frac{2k}{d}\right) \left(\frac{1}{\sqrt{d-1}}\right)^k, \text{ where } k = \text{dist}(u, v),$$

provided that $\text{var } X_v < \infty$. (This is sharp.)

Theorem(Backhausz, Gerencsér, H, Vizer)

If two connected subsets $V_1, V_2 \subset V(T_d)$ have large distance, then they are “almost independent” in the following sense: for an arbitrary factor X , any function f_1 of $(X_v)_{v \in V_1}$ and any function f_2 of $(X_v)_{v \in V_2}$ have small correlation, essentially of (the optimal) order $1/(\sqrt{d-1})^k$.

Do we really need connectedness?

Correlation bounds

Let $X = (X_v)_{v \in V(T_d)}$ be a factor of IID process on $\mathbb{R}^{V(T_d)}$. A natural question is “how independent” the random variables X_v are.

Theorem(Backhausz, Szegedy, Virág)

$$|\text{corr}(X_u, X_v)| \leq \left(k + 1 - \frac{2k}{d}\right) \left(\frac{1}{\sqrt{d-1}}\right)^k, \text{ where } k = \text{dist}(u, v),$$

provided that $\text{var } X_v < \infty$. (This is sharp.)

Theorem(Backhausz, Gerencsér, H, Vizer)

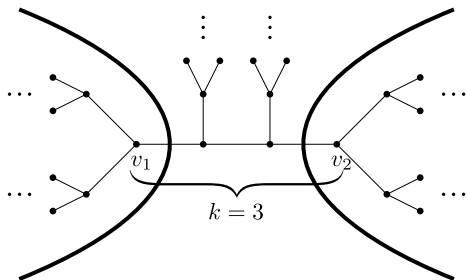
If two connected subsets $V_1, V_2 \subset V(T_d)$ have large distance, then they are “almost independent” in the following sense: for an arbitrary factor X , any function f_1 of $(X_v)_{v \in V_1}$ and any function f_2 of $(X_v)_{v \in V_2}$ have small correlation, essentially of (the optimal) order $1/(\sqrt{d-1})^k$.

Do we really need connectedness? **Yes!**

Outline of the proof

Let \tilde{T}_{d-1} denote the rooted $(d-1)$ -ary tree.

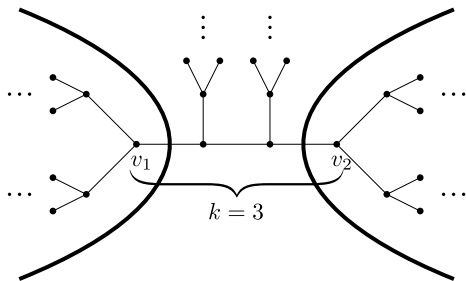
- Step 1: we might assume that V_1 and V_2 are both isomorphic to \tilde{T}_{d-1} and their roots have distance k .



Outline of the proof

Let \tilde{T}_{d-1} denote the rooted $(d-1)$ -ary tree.

- Step 1: we might assume that V_1 and V_2 are both isomorphic to \tilde{T}_{d-1} and their roots have distance k .

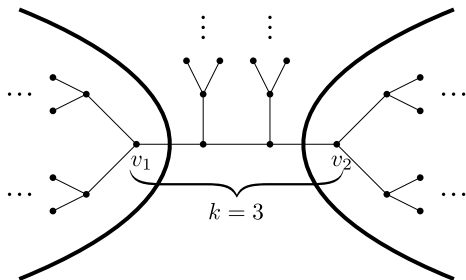


- Step 2: We claim that $|\text{corr}(f_1(X), f_2(X))|$ is maximized by functions f_1 and f_2 that are invariant under the automorphism group of \tilde{T}_{d-1} .

Outline of the proof

Let \tilde{T}_{d-1} denote the rooted $(d-1)$ -ary tree.

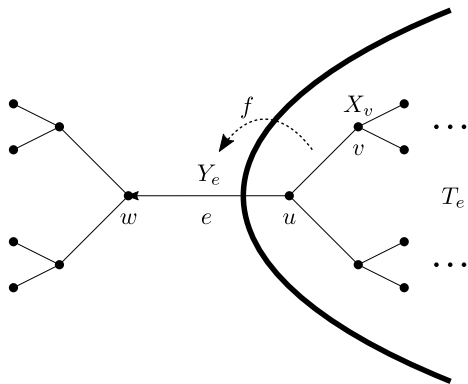
- Step 1: we might assume that V_1 and V_2 are both isomorphic to \tilde{T}_{d-1} and their roots have distance k .



- Step 2: We claim that $|\text{corr}(f_1(X), f_2(X))|$ is maximized by functions f_1 and f_2 that are invariant under the automorphism group of \tilde{T}_{d-1} .
- Step 3: in fact, they should “come from” the same $\text{Aut}(\tilde{T}_{d-1})$ -invariant measurable function $f: M^{V(\tilde{T}_{d-1})} \rightarrow \mathbb{R}$.

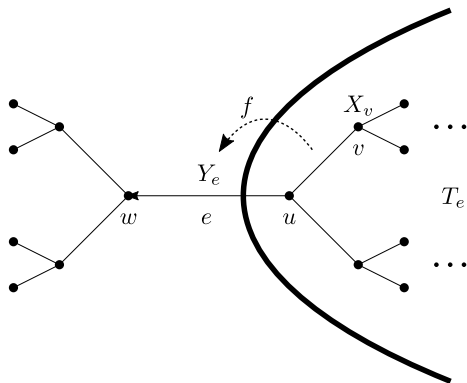
Outline of the proof

- Step 4: given such a function f , for any directed edge e of T_d , apply f to the (labelled) subgraph “behind” e and write its value on e . The process we obtain on the directed edge set $E(T_d)$ will be a factor of IID process.



Outline of the proof

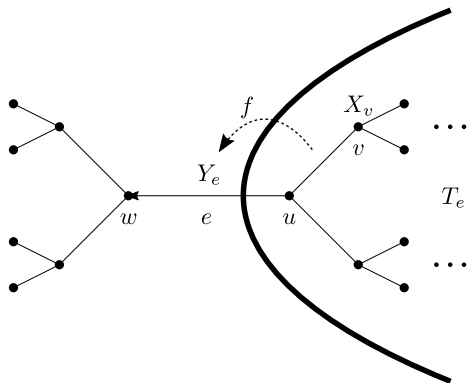
- Step 4: given such a function f , for any directed edge e of T_d , apply f to the (labelled) subgraph “behind” e and write its value on e . The process we obtain on the directed edge set $E(T_d)$ will be a factor of IID process.



- Step 5: we prove a correlation decay result similar to Backhausz-Szegedy-Virág but for directed edges instead of vertices.

Outline of the proof

- Step 4: given such a function f , for any directed edge e of T_d , apply f to the (labelled) subgraph “behind” e and write its value on e . The process we obtain on the directed edge set $E(T_d)$ will be a factor of IID process.



- Step 5: we prove a correlation decay result similar to Backhausz-Szegedy-Virág but for directed edges instead of vertices.
- Step 6: to finish Step 5 we need to estimate the norms of the powers of the non-backtracking operator.

Step 3: a lemma

Let (A, \mathcal{F}) be an arbitrary measurable space. Suppose that

- X_1, X_2 are (A, \mathcal{F}) -valued random variables;
- X_1 and X_2 are exchangeable, that is, (X_1, X_2) and (X_2, X_1) have the same joint distribution;
- there exists a constant $\alpha \geq 0$ with the property that for any measurable $f: A \rightarrow \mathbb{R}$ we have

$$|\text{corr}(f(X_1), f(X_2))| \leq \alpha \quad (*)$$

provided that $f(X_1)$ has finite variance.

Step 3: a lemma

Let (A, \mathcal{F}) be an arbitrary measurable space. Suppose that

- X_1, X_2 are (A, \mathcal{F}) -valued random variables;
- X_1 and X_2 are exchangeable, that is, (X_1, X_2) and (X_2, X_1) have the same joint distribution;
- there exists a constant $\alpha \geq 0$ with the property that for any measurable $f: A \rightarrow \mathbb{R}$ we have

$$|\text{corr}(f(X_1), f(X_2))| \leq \alpha \quad (*)$$

provided that $f(X_1)$ has finite variance.

Then for any measurable functions $f_1, f_2: A \rightarrow \mathbb{R}$

$$|\text{corr}(f_1(X_1), f_2(X_2))| \leq \alpha$$

provided that $f_1(X_1)$ and $f_2(X_2)$ have finite variances.

Proof of the lemma

- We might assume that $\text{var}(f_1(X_1)) = \text{var}(f_2(X_2)) = 1$.

Proof of the lemma

- We might assume that $\text{var}(f_1(X_1)) = \text{var}(f_2(X_2)) = 1$.
- Since X_1 and X_2 are exchangeable we have

$$\text{cov}(f_1(X_1), f_2(X_2)) = \text{cov}(f_1(X_2), f_2(X_1)).$$

Proof of the lemma

- We might assume that $\text{var}(f_1(X_1)) = \text{var}(f_2(X_2)) = 1$.
- Since X_1 and X_2 are exchangeable we have

$$\text{cov}(f_1(X_1), f_2(X_2)) = \text{cov}(f_1(X_2), f_2(X_1)).$$

- It follows that

$$\begin{aligned} \text{corr}(f_1(X_1), f_2(X_2)) &= \text{cov}(f_1(X_1), f_2(X_2)) \\ &= \frac{1}{4} \left(\text{cov}((f_1 + f_2)(X_1), (f_1 + f_2)(X_2)) - \text{cov}((f_1 - f_2)(X_1), (f_1 - f_2)(X_2)) \right). \end{aligned}$$

Proof of the lemma

- We might assume that $\text{var}(f_1(X_1)) = \text{var}(f_2(X_2)) = 1$.
- Since X_1 and X_2 are exchangeable we have

$$\text{cov}(f_1(X_1), f_2(X_2)) = \text{cov}(f_1(X_2), f_2(X_1)).$$

- It follows that

$$\begin{aligned} \text{corr}(f_1(X_1), f_2(X_2)) &= \text{cov}(f_1(X_1), f_2(X_2)) \\ &= \frac{1}{4} \left(\text{cov}((f_1 + f_2)(X_1), (f_1 + f_2)(X_2)) - \text{cov}((f_1 - f_2)(X_1), (f_1 - f_2)(X_2)) \right). \end{aligned}$$

- Using the triangle inequality and applying (*) to the function $f = f_1 + f_2$ and to $f = f_1 - f_2$ we obtain that

$$\begin{aligned} |\text{corr}(f_1(X_1), f_2(X_2))| &\leq \frac{\alpha}{4} \left(\text{var}((f_1 + f_2)(X_1)) + \text{var}((f_1 - f_2)(X_1)) \right) \\ &= \frac{\alpha}{4} \left(2 \text{var}(f_1(X_1)) + 2 \text{var}(f_2(X_1)) \right) = \alpha. \end{aligned}$$