

① $X_t = (B_t^1)^2 + \dots + (B_t^n)^2)^{1/2}, n \geq 2.$

$$Y_t = X_t^2$$

$$Y_t = (B_t^1)^2 + \dots + (B_t^n)^2$$

$$dY_t = 2 \sum_{i=1}^n B_t^i dB_t^i + \sum_{i,j=1}^n \langle dB_t^i, dB_t^j \rangle dt = ndt + 2 \sum_{i=1}^n B_t^i dB_t^i = ndt + 2\sqrt{Y_t} \sum_{i=1}^n \frac{B_t^i}{\sqrt{B_t^i \cdot (B_t^i)^2}} dB_t^i = ndt + 2\sqrt{Y_t} d\tilde{B}_t$$

? $d\tilde{B}_t$ $\langle \tilde{B}_t \rangle = t \Rightarrow \tilde{B}_t$ - броуновское движение

$$X_t = \sqrt{Y_t}$$

$$dX_t = \frac{1}{2\sqrt{Y_t}} dY_t - \frac{1}{2\sqrt{Y_t}} \cdot Y_t/dt = \frac{1}{2X_t} (ndt + 2X_t d\tilde{B}_t) - \frac{1}{X_t} dt = \frac{n-1}{2X_t} dt + d\tilde{B}_t$$

② $\beta_k(t) = \mathbb{E}[B_t^k], k \geq 2$

$$dB_t^k = k B_t^{k-1} dB_t + \frac{1}{2} k(k-1) B_t^{k-2} dt$$

$$B_t^k = \int_0^t k B_s^{k-1} dB_s + \int_0^t \frac{1}{2} k(k-1) B_s^{k-2} ds \quad | \mathbb{E}$$

$$\mathbb{E}[B_t^k] = \beta_k(t) = \frac{1}{2} k(k-1) \int_0^t \mathbb{E}[B_s^{k-2}] ds = \frac{1}{2} k(k-1) \int_0^t \beta_{k-2}(s) ds.$$

$$k=2: \frac{1}{2} \cdot 2 \cdot 1 \cdot \int_0^t 1 ds = t$$

③ $\begin{pmatrix} dX_1 \\ dX_2 \end{pmatrix} = \frac{1}{2} \begin{pmatrix} X_1 \\ X_2 \end{pmatrix} dt + \begin{pmatrix} X_1 \\ X_2 \end{pmatrix} dB_t$

$$\begin{pmatrix} X_1 \\ X_2 \end{pmatrix} = \begin{pmatrix} \sinh(B_t) \\ \cosh(B_t) \end{pmatrix} \quad \begin{matrix} \alpha \sinh + \beta \cosh \\ \alpha \cosh + \beta \sinh \end{matrix} \quad \begin{matrix} X_1^0 = \dots \\ X_2^0 = \dots \end{matrix}$$

④ a) $dX_t = X_t dt + dB_t, X_0 = x$

$$F_t = e^{-t}$$

$$d(F_t X_t) = d(e^{-t} X_t) = -e^{-t} X_t dt + e^{-t} dX_t = -e^{-t} X_t dt + e^{-t} X_t dt + e^{-t} dB_t$$

$$d(e^{-t} X_t) = e^{-t} dB_t$$

$$e^{-t} X_t = \int_0^t e^{-s} dB_s + x$$

$$X_t = x e^t + \int_0^t e^{t-s} dB_s$$

c) $dX_t = 2dt + \alpha X_t dB_t, X_0 = x$

$$dF_t = \theta_t dt + r_t dB_t$$

$$d(F_t X_t) = F_t dX_t + X_t dF_t + dX_t dF_t = F_t(2dt + \alpha X_t dB_t) + X_t(\theta_t dt + r_t dB_t) + \alpha r_t X_t dt =$$

$$= (2F_t + \underbrace{\theta_t X_t + \alpha r_t X_t}_0) dt + (\underbrace{\alpha X_t F_t + r_t X_t}_0) dB_t.$$

$$\begin{cases} \theta_t + \alpha r_t = 0 \\ \alpha F_t + r_t = 0 \end{cases} \Rightarrow \begin{cases} r_t = -\alpha F_t \\ \theta_t = \alpha^2 F_t \end{cases}$$

$$dF_t = \alpha^2 F_t dt - \alpha F_t dB_t$$

$$F_t = F_0 \exp\left\{-\alpha B_t + \frac{1}{2} \alpha^2 t\right\}, F_0 = 1$$

$$d(F_t X_t) = 2F_t dt$$

$$X_t = F_t^{-1} \left(x + \int_0^t 2F_s ds \right) = \exp\left\{\alpha B_t - \frac{1}{2} \alpha^2 t\right\} \left(x + 2 \int_0^t \exp\left\{-\alpha B_s + \frac{1}{2} \alpha^2 s\right\} ds \right) =$$

$$= x \exp\left\{\alpha B_t - \frac{1}{2} \alpha^2 t\right\} + 2 \int_0^t \exp\left\{\alpha(B_t - B_s) - \frac{1}{2} \alpha^2 (t-s)\right\} ds.$$

