

Mechanism Design without Rational Expectations

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Abstract

Is incentive compatibility still necessary for implementation if we relax the rational expectations assumption? This paper characterizes the class of solution concepts requiring Bayesian Incentive Compatibility (BIC) for full implementation, showing that BIC is still necessary for full implementation of functions in a broad class of non-equilibrium solution concepts. This finding implies that some classical results, such as the impossibility of efficient bilateral trade (Myerson & Satterthwaite, 1983), are still relevant even if rational expectations do not hold. We argue this new approach to mechanism design is useful to explore how robust the results obtained with equilibrium solution concepts are.

Keywords: Mechanism Design, Bounded Rationality, Rational Expectations

JEL Codes: C72, D78, D82

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1 Introduction

Can a planner implement a given social goal by designing rules of interaction between agents, when these agents hold private information they can exploit to their advantage? The answer depends on how this interaction pans out, and the literature on mechanism design and implementation theory has extensively explored this problem using a variety of game-theoretic solution concepts.

While Bayesian Nash Equilibrium (BNE) remains a popular solution concept, insights from the experimental and behavioral literatures have highlighted that equilibrium models do not accurately predict agents' behavior in many settings. In these settings—for instance, when agents face a given interaction for the first time—the assumption that agents correctly anticipate their opponents' strategies (that is, that agents have rational expectations) feels particularly unpalatable.

It remains unclear whether solution concepts alternative to BNE allow for full implementation of a broader class of social choice rules than BNE does. Recent results about full implementation of social choice functions (SCFs) in non-equilibrium solution concepts suggest that the answer may be negative. For instance, de Clippel et al. (2019) and Kunitomo et al. (2023) prove that Bayesian Incentive Compatibility (BIC) is still necessary for full implementation of functions in level- k reasoning and interim correlated rationalizability (ICR). In contrast, results are more permissive for full level- k implementation of social choice sets (SCSs), for which BIC is no longer necessary (de Clippel et al., 2019).¹

This paper studies the limits of full implementation by characterizing the class of all solution concepts such that BIC is necessary for full implementation. Our results suggest that we can generally not expect to dramatically expand the set of implementable SCFs by moving to non-equilibrium solution concepts, while results about SCSs are more permissive.

Our novel approach turns on its head implementation theory's standard approach of

¹Results are more permissive for *partial* implementation of SCFs, as shown in Crawford (2021) and Kneeland (2022).

fixing a solution concept and then deriving necessary conditions for full implementation, allowing us to search for a deeper property linking all solution concepts requiring BIC for full implementation. Other than providing useful guidance about the possibility of implementing non-BIC social choice rules, these results allow us to extend some classical findings in the literature (for example, Myerson and Satterthwaite’s (1983) impossibility theorem) to a large class of solution concepts.

To achieve this goal, we propose a generalized model of full implementation that allows agents to hold arbitrary expectations about their opponents’ strategies. This model allows us to encompass all solution concepts in which agents best respond to their (possibly heterogeneous) expectations about their opponents. Our model nests the ones in Jackson (1991), de Clippel et al. (2019), Crawford (2021), Kneeland (2022), and Kunimoto et al. (2023) as special cases, unifying previous results about the necessity of BIC for full implementation.

For the case of implementation of SCFs, we show BIC is still necessary for implementation if and only if the solution concept satisfies a novel property we call Weak Solution Consistency (WSC). This property can be interpreted as requiring that, for each type of each agent, there exists a solution of the mechanism such that she does not have any incentive to mimic a different type. Unlike regular incentive compatibility, WSC does not imply that this solution is the same for all types of all agents.² Even if this property is not very restrictive, it is enough to establish the necessity of BIC, as full implementation of a function requires all the mechanism’s solutions to yield the outcome prescribed by the SCF.

Several solution concepts in the literature satisfy WSC—for instance, the level- k model of de Clippel et al. (2019), ICR (Kunimoto et al., 2023), and BNE (Jackson, 1991) satisfy this condition for any given mechanism. Notably, in the spirit of the so-called *Wilson Doctrine*, WSC (and thus the necessity of BIC) does not hinge on the assumption of common knowledge of rationality.³

²See discussion at the end of Section 2.

³From an epistemic standpoint, WSC is almost equivalent to requiring that each type of each agent knows (1) the type space and (2) that she can “mimic” a different type—that is, that she can play the action another type would play and induce the planner to implement the corresponding

By providing a characterization of the set of solution concepts that allow implementation of BIC SCFs, this paper also identifies which solution concepts allow for implementation of non-BIC functions. Cursed Equilibrium (CE; Eyster and Rabin 2005) and models with self-similar beliefs (Rubinstein and Salant, 2016) fall into the latter category, as they do not rule out the possibility that agents might not realize they could profitably mimic a different type.⁴ Existence of non-WSC solution concepts confirms that WSC has bite, and the characterization result hints at which solution concepts may be fruitful to investigate to study implementation of non-BIC SCFs.

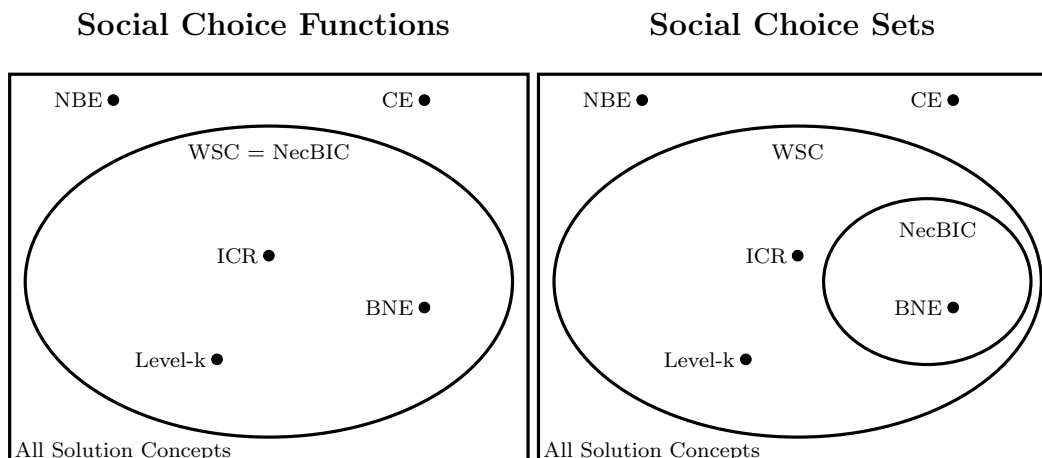


Figure 1: The class of solution concepts such that BIC is necessary for implementation (NecBIC) of all SCFs coincides with the class of WSC solution concepts for full implementation of SCFs (left) and it is a subset of the class of WSC solution concepts for full implementation of SCSs (right).

WSC is not enough to establish BIC is necessary for full implementation of SCSs (Figure 1): indeed, BIC is necessary only if the solution concept satisfies a property close to rational expectations.⁵ This necessity result is then relatively fragile, as it is unlikely to hold for most non-equilibrium solution concepts. WSC implies, however, that any implementable SCS must contain partially incentive compatible SCFs—that is, SCFs that provide

⁴Other models capture projection of a player’s own type or preferences—for instance Breitmoser (2019) and Gagnon-Bartsch et al. (2021). Even if our framework can capture these solution concepts, we will not discuss them in this paper.

⁵The solution concept of de Clippel et al. (2019) is a case in point: even if their level- k reasoning model satisfies WSC, they show in their Example 2 that it is possible to implement non-BIC SCSs.

only some types and agents with the right incentives not to misrepresent their private information. This last result confirms and extends the findings of Kneeland (2022) for level- k reasoning models.

The contrast between the results for implementation of SCFs and SCSs suggests that the necessity of BIC is mainly driven by the requirement that all solutions of the mechanism yield the same SCF when rational expectations do not hold. As agents understand that all solutions will lead to the same outcome, the same SCF must provide incentives to all agents not to misrepresent their type (that is, it must be BIC). If we allow different solutions to yield different outcomes instead (as in the case of full implementation of a SCS), each agent and type may believe a different solution of the mechanism (and the associated SCF) will obtain. Then, the planner no longer needs the same SCF to simultaneously incentivize all types of all agents unless rational expectations hold. In a sense, decoupling agents' expectations allows the planner to decouple the incentives she provides them. As assuming rational expectations makes this decoupling impossible, BIC is necessary for implementation in equilibrium solution concepts.

This discussion highlights a new tension that behavioral mechanism design faces: while having a unique outcome for all solutions offers starker predictions in applications, it often delivers restrictive results regarding incentive compatibility. This tension is absent in equilibrium solution concepts: regardless of the number of solution outcomes, the rational expectations assumption ensures BIC is necessary for implementation. This result follows again from the fact that both the uniqueness requirement and the rational expectations assumption do not allow the planner to decouple the incentives she provides to each agent from the ones she provides to other agents.

These results are important as they allow us to extend classical mechanism design findings to full implementation in any WSC solution concept. For the case of full implementation of functions, Section 6 considers three applications that extend to all WSC solution concepts: the Revenue Equivalence Theorem (Myerson, 1981), the impossibility of ex-post

efficient and budget-balanced bilateral trade (Myerson and Satterthwaite, 1983), and the impossibility of full surplus extraction in auctions. These applications highlight that much of the underlying economic intuition for these results does not hinge on the rational expectations assumption or the use of a particular equilibrium solution concept *per se*, and it remains central for the case of boundedly rational agents as well.

This paper advances the literature on mechanism design and bounded rationality by providing a methodology to answer open questions about implementation with and without rational expectations. Unlike previous works, this paper investigates how robust the necessity of BIC result is to changes in the solution concept. Previous papers focused instead on robustness in other model features—for example, Saran (2011) characterizes the domain of preferences on which the revelation principle holds, while Artemov et al. (2013) prove that the restrictiveness of robust virtual implementation stems from a particular zero-measure set of beliefs. This work also relates to approaches considering a planner with an inaccurate model of agents’ payoffs and beliefs, and in particular the literature about continuous (Oury and Tercieux, 2012; de Clippel et al., 2023) and robust (Bergemann and Morris, 2005) implementation. However, this paper focuses on a planner who has an accurate model of payoffs and beliefs but who is not sure how these map to the outcomes of strategic interaction, and it studies how sensitive restrictions on the set of implementable SCFs (such as BIC) are to changes in this mapping.

Our approach is relevant to the study of different implementation frameworks or necessary conditions as well. For instance, de Clippel et al. (2023) show that imposing the continuity requirement on level- k implementation does not make it significantly more restrictive as it does for BNE implementation. This result could be extended by characterizing the class of solution concepts for which it holds, highlighting what properties of the solution concept cause continuous implementation to impose significant additional restrictions on the class of implementable SCFs.

2 Model

The goal of the social planner is to select an alternative from a set A , conditional on some information privately held by the agents in set I . As usual in the literature, incomplete information is modeled by assuming that there exists a set of types T_i for each agent $i \in I$ and that each agent knows her type but not the type of other players. Let $T = \times_{i \in I} T_i$ be the set of all possible type profiles.

Agents' (interim) beliefs about the types of their opponents are denoted as $p_i : T_i \rightarrow \Delta(T_{-i})$ —that is, when an agent is of type t_i , she believes other players are of types t_{-i} with probability $p_i(t_{-i}|t_i)$.⁶ Assume also that for all $t \in T$, there exists $t \in T$ such that t_{-i} belongs to the support of $p_i(\cdot|t_i)$.⁷ Preferences over lotteries have expected utility form, with Bernoulli utility $u_i : A \times T \rightarrow \mathbb{R}$. Abusing notation slightly, let $u_i(a, t)$ for $a \in \Delta(A)$ denote the utility agent i derives from lottery a when the type profile is t .

The social planner seeks to implement a social choice function $f : T \rightarrow \Delta(A)$, and she does so by designing a mechanism $\gamma = (\mu, S)$, where $S = \times_{i \in I} S_i$ is an action space and $\mu : S \rightarrow \Delta(A)$ is an outcome function. Let Γ denote the set of all possible mechanisms the planner can design. Once the planner has committed to a mechanism, agents choose a strategy profile $\sigma : T \rightarrow \Delta(S)$. We denote the set of such functions as Σ . For all $i \in I$, we let Σ_i denote the set of all functions $\sigma_i : T_i \rightarrow \Delta(S_i)$ and all functions Σ_{-i} denote the set of $\sigma_{-i} : T_{-i} \rightarrow \Delta(S_{-i})$. For the rest of the paper, we slightly abuse the notation above by considering $\mu(\sigma(t))$ to denote the lottery over A induced by $\sigma(t)$ under the outcome function μ .

Define a *solution concept* \mathcal{S} as a correspondence mapping each mechanism γ to a subset of the set of all strategy profiles Σ .⁸ We then say an SCF f is *fully implementable* whenever

⁶For example, we can take $p_i(t_{-i}|t_i)$ to be the Bayesian posterior stemming from a common prior distribution $q : T \rightarrow (0, 1)$ such that $q(T) = 1$.

⁷This assumption is not necessary for the argument, but it makes the notation more convenient by avoiding stating results in terms of equivalent SCFs.

⁸To be precise, \mathcal{S} maps the game induced by mechanism γ to a set of solutions. As the set of players, the type space, and the utility functions are taken as given, for the sake of brevity in the remainder of the paper let us say \mathcal{S} associates each mechanism γ with the set of its solutions $\mathcal{S}(\gamma)$.

(1) there exists a mechanism $\gamma \in \Gamma$ that has at least one solution and (2) every such solution yields the outcome prescribed by f . Formally, an SCF f is fully implementable in \mathcal{S} whenever there exists an implementing mechanism γ such that $\mathcal{S}(\gamma) \neq \emptyset$ and $\mu(\mathcal{S}(\gamma)) = f$. Moreover, let $\Gamma^{f,\mathcal{S}} \subseteq \Gamma$ denote the class of all such mechanisms.

In Section 4.2, we will generalize the discussion by assuming the planner seeks to implement a Social Choice Set F , where F is a non-empty collection of SCFs. We say F is fully implementable whenever there exists a mechanism $\gamma \in \Gamma$ such that $\mu(\mathcal{S}(\gamma)) = F$, and we denote the class of mechanisms implementing F as $\Gamma^{F,\mathcal{S}} \subseteq \Gamma$.

For the remainder of the paper, we will refer to *full implementation* simply as *implementation* unless otherwise specified. For implementation of function, we will moreover refer to the requirement that $\mu(\mathcal{S}(\gamma)) = f$ as the *uniqueness requirement*, as it demands that all solutions of the mechanism yield the very same SCF.

We say an SCF f is *Bayesian Incentive Compatible* (BIC) for agent i of type t_i whenever, for all $t'_i \in T_i$:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

That is, type t_i of agent i has no incentive to pretend to be of a different type in the direct mechanism associated with the SCF. We also say f is BIC whenever it is BIC for all $i \in I$ and $t_i \in T_i$, and that an SCS F is BIC whenever all $f \in F$ are BIC.

Similarly, we say f is *Strict-if-Responsive Bayesian Incentive Compatible* (SIRBIC) for type t_i of agent $i \in I$ whenever it is BIC for $t_i \in T_i$ and the inequality above is strict for all $t'_i \neq t_i$ such that $f(t'_i, t_{-i}) \neq f(t)$ for some $t_{-i} \in T_{-i}$. Again, f is SIRBIC whenever it is SIRBIC for all types of all agents, and F is SIRBIC if all SCF $f \in F$ are SIRBIC.

We derive most of our results about the necessity of BIC by imposing a mild requirement on the solution concept \mathcal{S} . This requirement can be interpreted as requiring that for each type t_i of agent i , a solution of the mechanism exists such that she has no incentive to play the strategy associated with a different type.

Definition 1 (Weak Solution Consistency (WSC)). *A solution concept \mathcal{S} satisfies WSC for a class of mechanisms $\tilde{\Gamma} \subseteq \Gamma$ whenever for all $\gamma \in \tilde{\Gamma}$, $i \in I$, and $t_i \in T_i$ there exists $\sigma^{i,t_i} \in \mathcal{S}(\gamma)$ such that for all $t'_i \in T_i$:*

$$\int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t), t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t'_i, t_{-i}), t), t) dp_i(t_{-i}|t_i).$$

We say \mathcal{S} satisfies WSC if it satisfies WSC for all $\gamma \in \Gamma$ such that $\mathcal{S}(\gamma) \neq \emptyset$.

Notice that this solution σ^{i,t_i} need not be the same for all players i as we do not require agents' expectations to be consistent. As we allow expectations to be type dependent, this solution need not be the same for any type t_i of player i either.⁹ This highlights that WSC is much weaker than incentive compatibility, which instead requires σ^{i,t_i} to be the same for all types of all players.¹⁰ Moreover, Definition 1 directly implies that a solution concept \mathcal{S} is WSC whenever $\tilde{\mathcal{S}} \subseteq \mathcal{S}$ for a WSC solution concept $\tilde{\mathcal{S}}$.

Finally, we make a few additional technical assumptions. To make sure expected utility is well defined over the spaces discussed in the paper, let A , T_i , and S_i be separable metrizable spaces endowed with the Borel sigma algebra; let product sets be endowed with the product topology; let the Bernoulli utility functions be bounded and continuous; and let SCF, mechanisms and strategies be measurable functions.

2.1 Modeling Expectations Explicitly

A key feature of rational expectations models is that agents' expectations turn out to be correct in equilibrium. For example, if σ is a BNE, player i expects her opponents to play σ_{-i} : agents expect their opponents to play exactly the strategy they are actually playing. This is no longer the case when dispensing the rational expectations assumption: agents may be responding to an incorrect conjecture about their opponents' strategies.

⁹About these points, see also Remark 2 in Kneeland (2022) and the discussion of weak Interim Rationalizable Monotonicity in Kunimoto et al. (2023).

¹⁰For more details, we refer the reader to the discussion of Total Weak Solution Consistency in Section 4.2.

It will sometimes be convenient to model more explicitly the expectations agents are responding to, and how they translate into a solution concept. For a given mechanism γ , let $e_{i,t_i} \in \Sigma_{-i}$ represent the expectations of type t_i of agent i about the strategy player by her opponents. The set of all possible expectations for mechanism γ is denoted as $\mathcal{E}(\gamma) = \times_{i \in I} \Sigma_{-i}$. As e_{i,t_i} is a strategy profile for players $j \neq i$, we sometimes evaluate it at t_{-i} ; thus, $e_{i,t_i}(t_{-i}) \in \Delta(S_{-i})$. To make the notation more compact, define a mapping $e_i : T_i \rightarrow \Sigma_{-i}$ that assigns e_{i,t_i} to each type $t_i \in T_i$ and denote as e any profile $(e_i)_{i \in I} \in \mathcal{E}(\gamma)$.

The formulation above implicitly assumes expectations are deterministic. However, given that we assume agents' preferences over lotteries admit an expected utility representation, this assumption does not cause further loss of generality. Agents are also allowed to expect their opponents' actions to be correlated as $e_{i,t_i} \in \Sigma_{-i}$, and we do not assume Σ_{-i} have a product structure. This formulation makes it possible to accommodate models such as the ICR model in Kunimoto et al. (2023).¹¹

Let then a *theory of expectations* E be any correspondence mapping each mechanism γ to a subset $E(\gamma)$ of $\mathcal{E}(\gamma)$. We interpret $E(\gamma)$ as the expectations the model allows agents to hold. For example, ICR implicitly rules out the possibility that agents expect one of their opponents to play a dominated strategy (see Section 5 for some examples of models of expectations). As in de Clippel et al. (2019) and Kunimoto et al. (2023), we can interpret $E(\gamma)$ as the set of expectation profiles the planner believes could happen with nonzero probability. This interpretation is reflected in the implementation concept defined below, which requires the outcome prescribed by f to prevail regardless of the expectation profile considered.

Define a *theory of response* as any correspondence $R : E \times \gamma \rightarrow \Sigma$. It is easy to see that the composition $\mathcal{S} = R \circ E$ is then a solution concept: \mathcal{S} maps each mechanism γ to a subset of Σ , which we can interpret as the mechanism's solutions. Formally, let σ is a solution of mechanism γ whenever $\sigma \in R(e)$ for $e \in E(\gamma)$.

¹¹See Dekel et al. (2007) for further discussion about the difference between independent and correlated interim rationalizability.

2.1.1 A Sufficient Condition for WSC

Modeling expectations and responses explicitly enables us to provide a sufficient condition for WSC that is both insightful and easy to check.

For all $\sigma_{-i} \in \Sigma_{-i}$, denote as $B_{i,t_i}(\sigma_{-i})$ the set of best replies for type t_i of i to the profile σ_{-i} .¹² That is, if $s_i \in B_{i,t_i}(\sigma_{-i})$, then for all $s'_i \in \Delta(S_i)$:

$$\int_{T_{-i}} u_i(\mu(s_i, \sigma_{-i}(t_{-i})), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(s'_i, \sigma_{-i}(t_{-i})), t) dp_i(t_{-i}|t_i).$$

Let $B(e)$ denote the set of $\sigma \in \Sigma$ such that for all $i \in I$ and $t \in T$, $\sigma_i(t_i) \in B_{i,t_i}(e_{i,t_i})$.

We then say a solution concept \mathcal{S} is *Solution Consistent* (SC) for mechanism γ whenever $R \subseteq B$ and for all $i \in I$ and $t_i \in T_i$ there exists $e \in E(\gamma)$ and $\sigma \in R(e)$ such that $(\sigma_i, e_{i,t_i}) \in \mathcal{S}(\gamma)$.¹³ We can see immediately that if \mathcal{S} satisfies SC for mechanism γ , then it satisfies WSC for the same mechanism. We say \mathcal{S} is SC whenever it is SC for all $\gamma \in \Gamma$ such that $\mathcal{S}(\gamma) \neq \emptyset$.

Solution Consistency is a rather mild requirement on \mathcal{S} , as it requires only that agents best respond to what they expect from their opponents and that the resulting strategy profile could be justified as being a solution of the mechanism. This means we can also interpret SC as demanding agents believe that their opponents display a minimal level of rationality: type t_i of i responds to the expectation her opponents respond to some expectation profile $e' \in E(\gamma)$ —that is, $(\sigma_i, e_{i,t_i}) \in \mathcal{S}(\gamma)$.

To make the interpretation above clearer, consider an example in which SC does not hold. This is the case, for example, if we assume all players are either of level 1 or 0 in the models of de Clippel et al. (2019), Crawford (2021), and Kneeland (2022). Suppose that, for all level-0 agents, the anchor is to play a dominated strategy. Then, profile $(\sigma_i(t'_i), \alpha_{-i}(t_{-i}))$

¹²The set of best responses should depend on the specific mechanism used as well, but we omit it to simplify notation.

¹³As $(\sigma_i, e_{i,t_i}) \in \mathcal{S}(\gamma)$ if and only if there exists $e' \in E(\gamma)$ such that $(\sigma_i, e_{i,t_i}) \in R(e')$, we can equivalently state that SC requires that for all $i \in I$ and $t_i \in T_i$ there exists $e, e' \in E(\gamma)$ and $\sigma \in R(e)$ such that $(\sigma_i, e_{i,t_i}) \in R(e')$.

can not be a solution of the mechanism, generating an inconsistency between the profile level-1 agents believe would prevail in the mechanism and what the solution concept actually is. Indeed, assuming all agents can be at least level 2 is crucial to ensure that SC holds for all $\gamma \in \Gamma$ (Section 5.1).

3 A Bilateral Trading Example

We can clarify the intuition about BIC’s necessity for full implementation of functions by considering the example of bilateral trade between level- k parties from Crawford (2021) and the discussion of said example in de Clippel et al. (2019).

Before moving to the example itself, we summarize how level- k models of behavior work. Level-0 players of type t_i are naïve and (non-strategically) play some anchor $\alpha_i(t_i)$, which is exogenous to the model. Level-1 agents instead believe their opponents to be level-0, thus they best respond to the belief their opponents are playing the anchor. We will say any such best response is a *level-1 consistent* strategy, denoted as σ^1 . For every level $k_i > 1$, agents of level k believe their opponents to be playing a *level- $(k - 1)$ consistent* strategy σ^{k_i-1} and best respond accordingly. We say profile σ is a solution of a game γ whenever there exists a combination of levels $\{k_i\}_{i \in I}$ such that $k_i > 0$ for all $i \in I$ and σ_i is level- k_i consistent for all $i \in I$.¹⁴

Suppose two risk-neutral parties trade an indivisible object with value c for the seller and v for the buyer, with both values distributed independently and uniformly between 0 and 1. The seller and the buyer respectively submit an ask a and a bid b for the object, and trade happens if and only if $b \geq a$. In that case, the trading price is $x = 0.5(a + b)$. The utility from not trading is 0 for both parties, while the utility from trading is $u_s = x - c$ and $u_b = v - x$ for the seller and the buyer, respectively.

¹⁴As in de Clippel et al. (2019), each agent’s type describes only her beliefs about the payoff-relevant state: as levels do not affect preferences, they are not part of the description of an agent’s type.

As in Crawford (2021), we assume that the agents' anchor is uniformly distributed over $[0, 1]$ and that both agents are of level $k = 1$. Then there exists an SCF f that is implementable but not BIC: the unique level-1 consistent strategies are to bid $\frac{2}{3}v$ for the buyer and to ask $\frac{2}{3}c + \frac{1}{3}$ for the seller, and the associated SCF stipulates that trade happens if and only if $2v \geq 2c + 1$ at a price of $\frac{1}{6}(2v + 2c + 1)$. As remarked by de Clippel et al. (2019), a buyer of value $v = 0.5$ would then have an incentive to imitate a buyer of type $v = 0.75$ to gain a positive payoff, violating BIC.

However, the same function is not implementable if the two agents could both be of level $k = 2$. de Clippel et al. (2019) highlight that playing $\frac{2}{3}v + \frac{1}{9}$ for $v \geq \frac{1}{3}$ and v otherwise is a best response for the buyer to the level-1 strategy of the seller. Similarly, playing $\frac{2}{3}c + \frac{2}{9}$ for $c \geq \frac{1}{3}$ and c otherwise is a best reply for the seller to a level-1 buyer. The strategies form a solution of the mechanism considered, but the mechanism fails to implement f as the two solutions lead to different outcomes.¹⁵

This discrepancy follows because full implementation of a SCF requires *all* solutions of the mechanism to yield the same outcome for each type profile $t \in T$ for the mechanism to implement an SCF f . The argument generalizes to any arbitrary mechanism $\gamma = (\mu, S)$. Suppose γ has a solution σ^1 (so that σ_i^1 is a best reply to α_{-i} for all agents), and suppose such a solution induces a non-incentive compatible SCF. Then, $\sigma' = (\sigma_i^2, \sigma_{-i}^1)$ is a solution of the mechanism whenever σ_i^2 is a best reply to σ_{-i}^1 , as player i is best responding to level-1 consistent strategies while her opponents are best responding to their anchors.¹⁶ Moreover, it cannot be the case that $\mu(\sigma^1) = \mu(\sigma')$. As σ^1 implements a non-BIC f , there exist $i \in I$,

¹⁵As a matter of fact, it is straightforward to check that two level-2 players would trade for $v = c = \frac{1}{4}$, while two level-1 players would not trade for those values as $\frac{1}{2} = 2v < 2c + 1 = \frac{3}{2}$.

¹⁶For the sake of simplicity, we implicitly assume that the set of level-2 consistent strategies is non-empty. See Section 5.1 for a general discussion.

$t_i, t'_i \in T_i$:

$$\begin{aligned} & \int_{T_{-i}} u_i(\mu(\sigma_i^2(t'_i), \sigma_{-i}^1(t_{-i})), t) dp_i(t_{-i}|t_i) = \\ & \int_{T_{-i}} u_i(\mu(\sigma_i^1(t'_i), \sigma_{-i}^1(t_{-i})), t) dp_i(t_{-i}|t_i) > \\ & \int_{T_{-i}} u_i(\mu(\sigma_i^1(t_i), \sigma_{-i}^1(t_{-i})), t) dp_i(t_{-i}|t_i) = \\ & \int_{T_{-i}} u_i(\mu(\sigma_i^2(t_i), \sigma_{-i}^1(t_{-i})), t) dp_i(t_{-i}|t_i) \end{aligned}$$

Therefore, σ^2 is not a best reply to σ^1 for at least one type t_i of player i . It must then be the case that $\mu(\sigma^1) \neq \mu(\sigma')$. This violates uniqueness, making it impossible for the mechanism to implement any non-incentive compatible SCF.¹⁷

While the argument above relies on the properties of level- k models (which are often solved recursively starting from the anchor), a similar result holds for a larger class of solution concepts: BIC is necessary for implementation in any solution concept such that agents correctly anticipate the (possibly stochastic) outcome of the mechanism in each state.

Equilibrium solution concepts clearly fall into this class, as agents correctly anticipate the strategies their opponents are using—that is, agents hold rational expectations. This class is broader, and it encompasses also solution concepts in which agents possibly hold heterogeneous and/or incorrect expectations about the strategies of their opponents. For instance, if we insist on full implementation of an SCF, the level- k reasoning model of de Clippel et al. (2019) and ICR (Kunimoto et al., 2023) fall into this class. Section 6.1 discusses how, for full implementation of functions, the impossibility result of Myerson and Satterthwaite (1983) generalizes to this broader class of solution concepts, confirming its robustness even outside the rational expectations paradigm.

¹⁷It would still be possible for the mechanism to implement a social choice *set*. In fact, de Clippel et al. (2019) prove BIC is no longer necessary for level- k implementation in this case.

4 Results

We prove that BIC is still a necessary condition for implementation of functions if and only if the solution concept satisfies a novel property we called Weak Solution Consistency (Section 4.1). This property can be interpreted as requiring that for each type of each agent, there exists a solution of the mechanism in which she does not want to imitate a different type. WSC is satisfied by several solution concepts that have been considered in the literature, with some notable exceptions (Section 5). WSC is not enough, however, to establish that BIC is necessary for full implementation of sets (Section 4.2), for which we need a condition stronger than WSC.

4.1 Full Implementation of Functions

There is a tight link between WSC and the necessity of BIC for implementation of functions: BIC remains a necessary condition whenever the solution concept is WSC for all mechanisms implementing f (and thus, whenever it is WSC for all mechanisms). Conversely, if f is BIC, \mathcal{S} is WSC for the whole class of implementing mechanisms $\Gamma^{f,\mathcal{S}}$.

Theorem 1. *If f is implementable in \mathcal{S} and \mathcal{S} is WSC for $\Gamma^{f,\mathcal{S}}$, then it is BIC. If f is BIC and implementable in \mathcal{S} , then \mathcal{S} is WSC for $\Gamma^{f,\mathcal{S}}$.*

As WSC solution concepts are such that an agent may mimic a different type, any impleme

As WSC solution concepts allows an agent of type t_i to “mimic” a different type t'_i by playing the action t'_i would play, any implementable SCF must provide agents an incentive not to misreport their type. The result then follows from the uniqueness requirement, which entails that the *same* SCF must incentivize all agents not to mimic a different type.

The full proof for the result is relegated to Appendix B. It is, however, instructive to discuss here a sketch of the argument for the “if” part to appreciate how WSC and the uniqueness requirement of full implementation drive the final result. The key step of the

proof involves noticing that whenever a solution σ of mechanism γ exists such that for type t_i and all $t'_i \in T_i$:

$$\int_{T_{-i}} u_i(\mu(\sigma(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

Then, as any f implemented by γ is such that $\mu(\sigma) = f$ by the uniqueness requirement of full implementability, the inequality above yields:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

WSC ensures that such a solution $\sigma \in \mathcal{S}$ exists for all $i \in I$ and $t_i \in T_i$: then, by the uniqueness requirement, it follows that all such solutions will yield f as an outcome. This is enough to establish that f is indeed BIC.

As argued below, the class of WSC solution concepts is rather broad, and it includes the level- k model of de Clippel et al. (2019), BNE, and ICR (Dekel et al., 2007). For an example of a WSC solution concept not yet considered in the literature, see the discussion about Δ -rationalizability in Section 5.2.¹⁸

4.1.1 Necessity of SIRBIC

We can use E and R to show that the necessity of SIRBIC is a byproduct of the assumption that all best replies to an agent's expectations concur to form a solution of the mechanism, rather than to the use of a non-equilibrium solution concept. This is the case, for example, in de Clippel et al. (2019) and Kunimoto et al. (2023).

Theorem 2. *Suppose f is BIC and implementable in \mathcal{S} . If $R = B$, then f is SIRBIC.*

That is, if all best replies to a profile of expectations are solutions to the mechanism (as is the case for the examples discussed in Section 5), SIRBIC obtains for free from BIC and

¹⁸Although the tools described in this paper can be used to investigate the necessity of BIC for implementation in other solution concepts as well, such an endeavor falls beyond this paper's scope.

implementability.

4.2 Full Implementation of Sets

The results in Section 4.1 suggest that the necessity of BIC is robust even if we consider non-equilibrium solution concepts for the case of full implementation of functions. This section considers implementation of social choice *sets* instead. de Clippel et al. (2019) and Kneeland (2022) prove that implementation of sets is more permissive than implementation of functions, as incentive compatibility of F is not necessary for implementation. Theorem 3 proves these positive results are due to the relaxation of the uniqueness requirement.

Theorem 3. *If F is implementable in WSC \mathcal{S} , then for all $i \in I$ and $t_i \in T_i$, there exists $f^{i,t_i} \in F$ that is BIC for i and t_i . Conversely, if F is implementable and there exists $f^{i,t_i} \in F$ that is BIC for i and t_i , then \mathcal{S} is WSC for $\Gamma^{F,\mathcal{S}}$.*

This result generalizes the standard incentive compatibility constraint, showing that only a form of *partial* incentive compatibility is necessary for implementation of sets. Incentive constraints can be satisfied through a different function f^{i,t_i} for each agent and type.¹⁹ A key implication is that the planner may be able to promise each type of each agent a different incentive f^{i,t_i} , exploiting heterogeneity in expectations across agents and types. Conversely, BIC requires the same function f to satisfy the incentive constraints of all players and types, imposing $f^{i,t_i} = f^{j,t_j}$ for all $i, j \in I$, $t_i \in T_i$, and $t_j \in T_j$. This provides intuition as to why implementation of sets is much more permissive than implementation of functions: as the planner is not restricted to a unique outcome for all solutions, she can decouple the incentives provided to each type of each player, possibly allowing for implementation of sets that do not contain any incentive compatible SCF.

We can also characterize the set of solution concepts that make BIC necessary for implementation when the uniqueness requirement is dropped. As the discussion of Theorem 3

¹⁹This point is similar to the one Kneeland (2022) makes about level- k models.

suggests, this class will feature concepts in which beliefs are consistent across players and types.

Definition 2 (Total Weak Solution Consistency (TWSC)). *We say a solution concept \mathcal{S} is TWSC for mechanism γ whenever for all $\sigma \in \mathcal{S}$, $i \in I$, $t_i, t'_i \in T_i$:*

$$\int_{T_{-i}} u_i(\mu(\sigma(t)), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma_i(t'_i, t_{-i})), t) dp_i(t_{-i}|t_i).$$

TWSC requires *all* solutions of the mechanism to be incentive compatible, and it is almost equivalent to BNE. The only difference is that for all $i \in I$, TWSC requires $\sigma_i(t_i)$ to be a better (rather than best) reply than $\sigma_i(t'_i)$ to profile σ_{-i} .

Theorem 4. *If F is implementable in TWSC \mathcal{S} , then it is BIC. If F is implementable and BIC, then \mathcal{S} is TWSC for $\Gamma^{F, \mathcal{S}}$.*

Theorem 4 suggests that, whenever F is not a singleton, the necessity of BIC is a more “fragile” result that follows very restrictive assumptions about the solution concept. This fragility arises because a non-singleton F allows different players to believe different outcomes will prevail in the mechanism. Therefore, it becomes no longer necessary for the *same* outcome to simultaneously provides incentives not to misrepresent their private information to each type and agent.

This intuition is confirmed by the fact that TWSC and WSC are equivalent for all mechanisms yielding the same outcome for all solutions. Therefore, in the non-rational expectations case, the BIC restriction on the class of implementable social choice rules can be imputed to the insistence on the uniqueness requirement—that is, on insisting on fully implementing an SCF.

Theorem 3 provides a weaker result than the one obtained from Kneeland (2022) for level- k implementation. In this case, we can make use of E in a more explicit way to bridge the gap between the two by requiring expectations to not depend on each agent’s type.²⁰

²⁰It would be possible to express the results below in terms of a modified WSC condition as well

We say expectations are *type-independent* whenever for all $\gamma \in \Gamma$ and $e \in E(\gamma)$, we have $e_{i,t_i} = e_{i,t'_i}$ for all $i \in I$ and $t_i, t'_i \in T_i$.

We can then strengthen the if part of Theorem 3 as follows.

Theorem 5. *If F is implementable in SC \mathcal{S} and expectations are type-independent, for all $i \in I$ there exists $f^i \in F$ that is BIC for i .*

Theorem 5 tells us that if expectations are constant with respect to i 's type, then the same SCF f^i must provide all types $t_i \in T_i$ with an incentive not to mimic another type.²¹ As for the difference between Theorem 1 and Theorem 3, the comparison of Theorem 3 and Theorem 5 highlights how heterogeneity in expectations leads to a larger class of implementable social choice rules.

5 Examples

As argued in the previous section, WSC and SC do not seem to be very restrictive. It is indeed satisfied by various solution concepts proposed in the literature: BNE (Jackson, 1991), level- k reasoning (de Clippel et al., 2019; Kneeland, 2022), and ICR (Kunimoto et al., 2023).

WSC, in contrast, is not satisfied by Eyster and Rabin's (2005) Cursed Equilibrium and by a solution concept in which agents project on their opponents their own actions akin to self-similarity of Rubinstein and Salant (2016). Informally, this is because these models are such that the profile of strategies formed by an agent's expectations and her response to those expectations is generally not a solution of the mechanism. These novel examples, together with Crawford's (2021) level- k model with no level-2 agents, serve to confirm that WSC does indeed have bite.

by substituting the qualifier “for all $i \in I$ and $t_i \in T_i$ ” with “for all $i \in I$.” However, stating the results in terms of expectations seems to be more intuitive.

²¹For the result to go through, the argument in the proof of Theorem 5 requires only that there exists one type-independent expectation in $E(\gamma)$ for each agent.

5.1 Level- k Reasoning

The discussion in this section builds on the models of de Clippel et al. (2019) and Kneeland (2022), which assume that any profile of levels k_i is possible, as long each level is lower than an upper bound $\bar{k} \geq 2$ —that is, $k_i \leq \bar{k}$ for all $i \in I$.

Let $\alpha_{-i} : \Gamma \rightarrow \Sigma_{-i}$ be any function assigning a profile of anchors to each mechanism $\gamma \in \Gamma$. For each agent $i \in I$, let $S_{-i}^1(\gamma|\alpha)$ denote the set of all level-1 consistent strategies $\sigma_{-i} : T_{-i} \rightarrow \Delta(S_{-i})$. Similarly, we denote the set of best replies to *level- $(k_i - 1)$ consistent* strategy profiles as the set of *level- k_i consistent* strategies $S_{-i}^{k_i}(\gamma|\alpha)$.

We can now characterize the set of solutions for each mechanism γ by setting $R = B$ and $E = E^{K,\alpha}$, where:

$$E^{K,\alpha}(\gamma) = \{e \in \mathcal{E} : e_{i,t_i} \in \{\alpha_{-i}(\gamma)\} \cup \{\cup_{1 \leq k_i \leq \bar{k}} S_{-i}^{k_i-1}(\gamma|\alpha)\}, e_{i,t_i} = e_{i,t'_i}, \text{ for all } i \in I, t_i, t'_i \in T_i\}.$$

That is, the set of all $e \in \mathcal{E}$ is such that each player i expects the remaining players to play the anchor ($e_i \in \alpha_{-i}(\gamma)$) or to best respond as players of some level $k_i - 1$ ($e_i \in \cup_{1 \leq k_i \leq K} S_{-i}^{k_i-1}(\mu|\alpha)$). It is immediately apparent that any strategy profile such that each player's strategy is level- k_i consistent for $k_i \geq 1$ is a solution of the mechanism.²²

This solution concept satisfies SC for all $\gamma \in \Gamma$. Because $\bar{k} \geq 2$, $E^{K,\alpha}(\gamma)$ contains at least one e such that $e_i \in S_{-i}^1(\gamma|\alpha)$. Consider, then, that for all $i \in I$ and $t_i \in T_i$, any $\sigma \in B(e) = R(e)$. It is clear, then, that $(\sigma_i, e_i) \in \mathcal{S}(\gamma)$ because σ_i is a level-2 consistent strategy and e_i is a profile of level-1 consistent strategies.

The assumption that $\bar{k} \geq 2$ (de Clippel et al., 2019; Kneeland, 2022) is useful to exclude pathological cases in which a player can only expect her opponent to play the anchor. This clarifies why the findings of de Clippel et al. (2019) and Kneeland (2022) differ from those in Section 4.1 of Crawford (2021), which instead proves it is possible to implement non-BIC SCFs even when the solution is unique. This possibility result arises because in that setup

²²In this case, expectations are type independent, allowing for a slightly stronger result about full implementation of SCSs (Theorem 5).

Crawford (2021) considers level-1 players only, allowing for the possibility that SC does not hold.

5.2 Interim Correlated and Δ -Rationalizability

Kunimoto et al. (2023) study implementation using Interim Correlated Rationalizability (ICR) as a solution concept, finding that SIRBIC is a necessary condition for implementing SCFs.

Let $C = (C_i)_{i \in I}$ be a correspondence profile such that $C_i : T_i \rightarrow 2^{S_i}$ for all $i \in I$. Consider now the operator $b = (b_i)_{i \in I}$ iteratively eliminating strategies that are never a best response:

$$b_i(C)[t_i] \equiv \left\{ \begin{array}{l} \exists \lambda_i \in \Sigma_{-i} \text{ such that:} \\ s_i \in S_i : (1) \text{ supp}(\lambda_i(t_{-i})) \subseteq C_{-i}(t_{-i}); \\ (2) s_i \in \arg \max_{s'_i} \int_{T_{-i}} u_i(\mu(s'_i, \sigma_{-i}(t_{-i})), t) dp_i(t_{-i}|t_i) \end{array} \right\}$$

As argued in Kunimoto et al. (2023), by Tarski's theorem, there exists a largest fixed point of b , which is denoted as $C^{\gamma(T)}$. The authors then require that, for f to be implementable, there must exist a mechanism such that (1) the desired outcome obtains for all rationalizable strategy profiles and (2) each type t_i has at least one rationalizable action.

We can then show that the class of ICR strategy profiles can be characterized by the following pair (E^{ICR}, R^{ICR}) :²³

$$E^{ICR}(\gamma) = \{e \in \mathcal{E} : \text{supp}(e_{i,t_i}(t_{-i})) \subseteq C_{-i}^{\gamma(T)}(t_{-i})\}$$

$$R^{ICR}(e) = \{\sigma \in \Sigma : \sigma \in B(e), |\text{supp}(\sigma(t))| = 1 \text{ for all } t \in T\}$$

This follows because $\mathcal{S}^{ICR}(\gamma) = R^{ICR}(E^{ICR}) = C^{\gamma(T)}$ for all $\gamma \in \Gamma$. In fact, $\sigma \in B(e)$

²³The requirement that $|\text{supp}(\sigma(t))| = 1$ for all $t \in T$ is due to the fact we focus on *pure* rationalizable actions, as usual in this literature.

for $e \in E(\gamma)$ implies that the unique profile s in σ 's support is rationalizable, and thus it implies that $\sigma \in C^{\gamma(T)}$ and $\mathcal{S} \subseteq C^{\gamma(T)}$. Conversely, suppose $\sigma \in C^{\gamma(T)}$. then for all $i \in I$ and $t_i \in T_i$, there exists a $\lambda_i \in C_{-i}^{\gamma(T)}$ to which $\sigma_i(t_i)$ is a best reply. Setting $e_{i,t_i} = \lambda_i$ is then enough to achieve $C^{\gamma(T)} \subseteq \mathcal{S}$.

ICR satisfies SC for a large class of mechanisms $\gamma \in \Gamma$ —in particular, those in which $B_i(e_{i,t_i}) \neq \emptyset$ for all $i \in I$ and $t_i \in T_i$ —for instance, if A is finite as in Kunimoto et al. (2023). Then, for any solution $\sigma \in \mathcal{S}^{ICR}$ and $\tilde{\sigma}_i \in B_i(\sigma_{-i})$, we have $(\tilde{\sigma}_i, \sigma_{-i}) \in \mathcal{S}^{ICR}(\gamma)$ as $\sigma \in \mathcal{S}^{ICR}(\gamma)$ entails that σ_{-i} is rationalizable for all agents $j \neq i$ and that $\tilde{\sigma}_i$ is rationalized by the belief that i 's opponents are playing σ_{-i} .

The same argument applies even if we require, similarly to Δ -rationalizability (Battigalli and Siniscalchi, 2003), that agents' beliefs about their opponents' strategies lie in a pre-specified set. For each $i \in I$ and $t_i \in T_i$, let Δ^i map each mechanism Γ to a set of “allowed” beliefs $\Delta^i(\gamma)$. Let $\Delta = (\Delta^i)_{i \in I}$. We can then redefine the operator b as follows:

$$b_i(C)[t_i] \equiv \left\{ \begin{array}{l} \exists \lambda_i \in \Delta^i \subseteq \Sigma_{-i} \text{ such that:} \\ s_i \in S_i : \quad (1) \text{ supp}(\lambda_i(t_{-i})) \subseteq C_{-i}(t_{-i}); \\ \quad \quad \quad (2) s_i \in \arg \max_{s'_i} \int_{T_{-i}} u_i(\mu(s'_i, \sigma_{-i}(t_{-i})), t) dp_i(t_{-i}|t_i) \end{array} \right\}$$

Again, as b is a monotone operator, Tarski's theorem implies that there exists a largest fixed point, which we again denote as $C^{\gamma(T), \Delta}$. The same argument as above then shows that the class of Δ -rationalizable strategies \mathcal{S}^Δ can be characterized through the following pair:

$$E^\Delta(\gamma) = \{e \in \mathcal{E} : \text{supp}(e_{i,t_i}(t_{-i})) \subseteq C_{-i}^{\gamma(T), \Delta}(t_{-i})\}$$

$$R^\Delta(e) = \{\sigma \in \Sigma : \sigma \in B(e), |\text{supp}(\sigma(t))| = 1 \text{ for all } t \in T\}$$

Δ -rationalizable full implementation has not been considered in the literature, so it is not yet known whether BIC is necessary for full implementation.²⁴ There is no obvious

²⁴Artemov et al. (2013) use Δ -rationalizability as a solution concept. Differently from this paper, they study robust virtual implementation by imposing restrictions on the set of beliefs agents may

relation between the set of Δ -rationalizable profiles and equilibrium profiles either, as the relation depends on the restrictions imposed by Δ . For a simple example, focus on the following complete-information game:²⁵

		Player C		
		A	B	C
Player R	A	(2, 2)	(-2, -2)	(-2, -2)
	B	(-2, -2)	(1, -1)	(-1, 1)
	C	(-2, -2)	(-1, 1)	(1, -1)

This game admits only one pure-strategy equilibrium in which both players play A .²⁶ If Δ imposes no restriction on players' beliefs, any pure-strategy profile is Δ -rationalizable; therefore, any equilibrium is Δ -rationalizable as well. Suppose now we restrict agents' beliefs to assign positive probability to B and C only. As A is dominated when the opponent never plays A , any profile in which A is played is now not Δ -rationalizable, implying that the set of Δ -rationalizable profiles is disjoint from the set equilibrium profiles.

We can then use Theorem 1 and Theorem 3 to derive a novel result about the necessity of BIC for Δ -rationalizable implementation by proving that \mathcal{S}^Δ is WSC whenever Δ does not rule out the possibility that agents believe that their opponents will play a pure strategy. That is, for all $i \in I$, let Δ^i contain all λ_i whose support is a singleton for all $t_{-i} \in T_{-i}$.²⁷ Consider again the class of mechanisms such that $B_i(e_{i,t_i}) \neq \emptyset$ for all $i \in I$ and $t_i \in T_i$. As the set of solutions is non-empty, there exists a pure strategy profile σ such that σ_j is rationalized by a belief λ_j in Δ^j for all $j \in I$. We then construct $\sigma^{i,t_i} = (\sigma_i^*, \sigma_{-i})$, where $\sigma_i^* \in B_{i,t_i}(\sigma_{-i})$. As σ_i^{i,t_i} is rationalized by $\sigma_{-i} \in \Delta^i$, and σ_j^{i,t_i} is rationalized by some belief in Δ^j for all $j \neq i$, it follows that $\sigma^{i,t_i} \in \mathcal{S}^\Delta$ and thus, as our choice of i and t_i was arbitrary, that \mathcal{S}^Δ is WSC.

have about their opponents' *types*.

²⁵We can think of it as a Bayesian game in which each player has only one type.

²⁶We focus on pure equilibria to keep our results comparable with those for Interim Correlated Rationalizability discussed above.

²⁷For the result to go through, it is enough that the set of Δ -rationalizable strategies for i 's opponents has a non-empty intersection with set Δ^i for all $i \in I$.

5.3 Bayesian Nash Equilibrium and Refinements

The setup proposed in this paper can capture Bayesian Nash equilibrium if we impose the following:

$$E^{BN}(\gamma) = \{e \in \mathcal{E}(\gamma) : \exists \sigma \in \times_{i \in I} \Sigma_i \text{ s.t. } e_{i,t_i} = \sigma_{-i} \text{ for all } i \in I, t_i \in T_i\}$$

$$R^{BN}(e) = \{\sigma \in B(e) : \sigma_{-i} = e_i \text{ for all } i \in I\}$$

It is clear then that the set of BNEs is equal to $R^{BN}(E^{BN}(\gamma)) = \mathcal{S}^{BN}(\gamma)$. In fact, if $\sigma \in \mathcal{S}^{BN}(\gamma)$, then $\sigma_i \in B(\sigma_{-i})$ for all $i \in I$. On the other hand, if σ is a BNE, it is immediate to notice that $(\sigma_{-i})_{i \in I} \in E^{BN}(\gamma)$ and thus that $\sigma \in R^{BN}(e)$. Moreover, as long as $E^{BN}(\gamma) \neq \emptyset$, $R^{BN}(E^{BN}(\gamma)) \neq \emptyset$ as well. In fact, R^{BN} just selects, among all profiles of best responses, the one satisfying rational expectations. \mathcal{S}^{BN} also satisfies SC for all $\gamma \in \Gamma$ because for all $i \in I$ and $t_i \in T_i$, the expectation profile $e' = (\sigma_{-i})_{i \in I}$ is such that $(\sigma_i, e_{i,t_i}) = \sigma \in B(e')$. A similar argument applies to refinements of BNE as well (as undominated BNE).

5.4 Cursed Equilibrium

Our setup can also capture the *Cursed Equilibrium* solution concept from Eyster and Rabin (2005). Cursed Equilibrium seeks to capture the intuition that agent underestimate the correlation between their opponents' types and actions. This is modeled by assuming agents best respond to the expectations that their opponents' actions will depend on their type with probability $(1 - \chi)$ and that they will not depend on their type with probability χ .

This leads to the following theory of behavior:

$$E^{CE}(\gamma) = \{e \in \mathcal{E}(\gamma) : \exists \sigma \in \times_{i \in I} \Sigma_i \text{ s.t. } e_{i,t_i} = \bar{\sigma}_{-i}(t_i, \cdot) \text{ for all } i \in I, t_i \in T_i\}$$

$$R^{CE}(e) = \{\sigma \in B(e) : \bar{\sigma}_{-i}(t_i, \cdot) = e_{i,t_i} \text{ for all } i \in I \text{ and } t_i \in T_i\},$$

where:

$$\bar{\sigma}_{-i}(t) = (1 - \chi)\sigma_{-i} + \chi \int_{T_{-i}} \sigma_{-i}(t_{-i}) dp_i(t_{-i}|t_i).$$

It is possible to prove that this solution concept is generally not WSC. Intuitively, the reason is that the payoff distribution that agents expect to achieve in common-value setups differs from the one the mechanism actually implements. For instance, a fully cursed ($\chi = 1$) agent i expects the payoff from playing the action associated with type t'_i to be $\int_{T_{-i}} u_i(f(t'_i, \bar{v}_{-i}), t) dp_i(t_{-i}|t_i)$ rather than $\int_{T_{-i}} u_i(f(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i)$, where ι represents the identity function. While the difference between these two expressions is immaterial for private-value setups, it typically is not for common-value ones.

To prove WSC is violated as well for any $\chi \in (0, 1]$, we can construct the following two-player game:

		Player C	
		A	B
Player R	A	t_R, t_C	$t_R + \zeta t_C, 0$
	B	$0, t_C + \zeta t_R$	$0, 0$

Where $t_i \in \{-1, 1\}$ for $i \in \{R, C\}$, each type profile happens with equal probability, and $\zeta \in (2, \frac{2}{1-\chi})$.²⁸ The only Cursed Equilibrium of this game is for type 1 to play A and for type -1 to play B .

The payoff of B is always 0 for either player. The payoff i expects from playing A is:

$$t_i - \frac{1}{2}(1 - \chi)\zeta(\sigma_{-i}(1)[A] - \sigma_{-i}(-1)[A]).$$

Type 1 will play A with probability 1 as:

$$1 - \frac{1}{2}(1 - \chi)\zeta > 0 \iff \zeta < \frac{2}{1 - \chi}.$$

²⁸In the discussion below, the argument focuses on the case of $\chi < 1$. The case of $\chi = 1$ follows from the same steps as long as $\zeta > 2$.

And type $t_i = -1$ will play B with probability 1 as:

$$-1 - \frac{1}{2}(1 - \chi)\zeta < 0 \iff \zeta > \frac{-2}{1 - \chi}.$$

There is therefore a pure Cursed Equilibrium in which both agents play A if their type is $t_i = 1$ and B otherwise. Moreover, this is the unique Cursed Equilibrium of the game, and it does not satisfy WSC. In fact, for type $t_i = 1$ of player i , $\zeta > 2$ implies that:

$$\frac{1}{2}t_i + \frac{1}{2}(t_i - \zeta) = 1 - \frac{1}{2}\zeta < 0.$$

Thus, type $t_i = 1$ would like to mimic type $t_i = -1$ if she was not ignoring the correlation between her opponents' strategies and types: Cursed Equilibrium then allows for the implementation of non-BIC SCFs.

5.5 Self-Similarity Equilibrium

To demonstrate the usefulness of our approach, we will discuss another solution concept that has not yet been studied in the implementation literature, and that aims to capture the fact that agents believe their opponents' actions are more similar to their own than they actually are—that is, the fact that agents project their own actions on their opponents (Rubinstein and Salant, 2016).

Let Γ^* be the class of all mechanisms such that $S_i = S^*$ for all $i \in I$. For each $\gamma \in \Gamma^*$ and $\chi \in (0, 1)$ we then define a *self-similarity equilibrium*:

$$E^{SSE}(\gamma) = \{e \in \mathcal{E}(\gamma) : \exists \sigma \in \times_{i \in I} \Sigma_i \text{ s.t. } e_{i,t_i} = (\tilde{\sigma}_{i,t_i}^j)_{j \neq i} \text{ for all } i \in I, t_i \in T_i\}$$

$$R^{SSE}(e) = \{\sigma \in B(e) : e_{i,t_i} = (\tilde{\sigma}_{i,t_i}^j)_{j \neq i} \text{ for all } i \in I, t_i \in T_i\},$$

where for all $i \in I$, $j \neq i$ and $t_{-i} \in T_{-i}$:

$$\tilde{\sigma}_{i,t_i}^j(t_{-i}) = (1 - \chi)\sigma_j(t_{-i}) + \chi\sigma_i(t_i).$$

The definition of E^{SSE} captures the fact that agents expect their opponents' actions to be closer to their own than they actually are: an agent's expectations are a linear combination of her own mixed action and their opponents' actual strategy.

We can prove SSE is not a WSC solution concept by considering the setup of Section 5.4 once again. As before, the expected payoff of B is always 0 for either player. The payoff i expects from playing A is:²⁹

$$t_i - \frac{1}{2}(1 - \chi)\zeta(\sigma_{-i}(1)[A] - \sigma_{-i}(-1)[A]).$$

So type 1 will play A with probability 1 as:

$$1 - \frac{1}{2}(1 - \chi)\zeta > 0 \iff \zeta < \frac{2}{1 - \chi}.$$

And type $t_i = -1$ will play B with probability 1 as:

$$-1 - \frac{1}{2}(1 - \chi)\zeta < 0 \iff \zeta > \frac{-2}{1 - \chi}.$$

There is, therefore, a unique SSE solution in which an agent of type 1 play A with probability 1 and an agent of type -1 plays B with probability 1. As above, the SCF this solution induces is not BIC for the values of ζ considered.

²⁹While the expected payoff is the same as in the Cursed Equilibrium case, the rationale is different: here agents underestimate the correlation between opponents' actions and types as they overestimate the correlation between their own actions and their opponents' ones.

6 Applications

The results in previous sections allow us to extend the results stemming from the necessity of BIC for implementation to all WSC solution concepts. We take as examples three classical results from the mechanism design literature: the impossibility of efficient bilateral trade (Myerson and Satterthwaite, 1983), the impossibility of full surplus extraction in auctions, and the Revenue Equivalence Theorem (Myerson, 1981). Our results confirm that the economic intuition behind these results extends to a wide range of boundedly rational setups.

6.1 Myerson-Satterthwaite’s Impossibility Theorem

Myerson and Satterthwaite (1983) show that efficient bilateral trade is impossible in the presence of private information, unless the planner steps in to cover some of the losses the agents face. As this result relies on the necessity of BIC for implementation in BNE, Theorem 1 allows us to extend it to all WSC solution concepts.

As in Myerson and Satterthwaite (1983), we consider a bargaining problem in which two agents (a buyer B and a seller S) bargain over the sale of an indivisible object that each agent values at t_i , where each t_i ’s distribution admits a continuous and positive pdf over the interval $[a_i, b_i]$, where $(a_S, b_S) \cap (a_B, b_B) \neq \emptyset$. We also assume that t_B is independent of t_S and that each agent knows her valuation and how the valuation of the other agent is distributed. The set of alternatives consists of all pairs (q, x) , where $q \in [0, 1]$ represents the probability that trade will happen and x indicates the amount transferred from the buyer to the seller. Bernoulli utilities u_i are additively separable in money and the value of the object, and agents are risk neutral.

Under these assumptions, Myerson and Satterthwaite (1983) prove that an implementing mechanism that assigns an object to the agent who values it the most is unable to ensure voluntary participation by both agents. Formally, an SCF is *ex-post efficient* if it allocates the object with probability 1 to the agent who values it the most—that is, $q(t) = 1$ whenever

$t_B > t_S$, and $q(t) = 0$ whenever $t_B < t_S$. Moreover, we say f is *individually rational* whenever $u_i(f(t), t) = q(t)t_i - x(t) \geq 0$ for all $i \in I$ and $t \in T$.

Myerson and Satterthwaite’s (1983) proof relies on showing there exists no SCF f that is simultaneously individually rational, ex post efficient, and BIC. The following corollary then follows immediately from Theorem 1:

Corollary 1. *If f is individually rational and ex-post efficient, it is not fully implementable in any WSC \mathcal{S} .*

Myerson and Satterthwaite (1983) highlight that it is impossible to find an ex-post efficient and individually rational SCF that is also incentive compatible for all types and agents *at the same time*. This finding extends the negative results de Clippel et al. (2019) and Crawford (2021) obtain for full implementation of SCFs in level- k reasoning.

Kneeland (2022) shows instead it is possible to fully implement an efficient and individually rational social choice *set*. Each agent can believe a different solution of the mechanism will obtain when F is not a singleton, allowing the planner to decouple the incentives she provides. That is, F must contain one SCF that is incentive compatible for each agent and type, but needs not contain an SCF that is incentive compatible for all types of all agents at the same time.

6.2 Impossibility of Full Surplus Extraction

If \mathcal{S} is WSC, the planner cannot implement any auction extracting all expected surplus from agents unless she excludes lower-ranked types from winning the object.

Suppose the planner is tasked with designing a mechanism to allocate a single unit of an indivisible object in exchange for the payment of a fee. Let the set of alternatives be defined as follows:

$$A = \{(q, x) \in [0, 1]^I \times \mathbb{R}^I : \sum_{i \in I} q_i \leq 1\}$$

That is, $f(t)$ assigns to each agent some probability of winning the object and a (non-contingent) monetary transfer. For a given f , denote as $q_i^f(t)$ the probability that agent i receives the object and denote as $x_i^f(t)$ the associated transfer to the planner from the agent getting the object. Assume, moreover, that $T \subseteq \mathbb{R}^I$ and types are determined by a commonly known joint distribution. The value of the object to agent i is determined according to a function v_i that is strictly increasing in i 's type, and Bernoulli utilities take the additively separable form $u_i(t) = v_i(t) - x_i$.

We then say a SCS F is *fully extractive* whenever the planner extracts the entire surplus in all states—that is, whenever $x_i^f(t) = q_i^f(t)v_i(t)$ for all $t \in T$ and $f \in F$. Moreover, we say F is *inclusive* whenever, for all $f \in F$ and $i \in I$ there exists $t \in T$ and $t'_i \in T_i$ such that $t'_i > t_i$ and $q_i^f(t) > 0$. Inclusivity requires that f does not prevent all types t_i that are ranked lower than t'_i from getting the object with positive probability no matter the type profile t_{-i} of other agents—that is, there must exist at least one type profile t_{-i} such that type t_i wins the object with positive probability. Ex-post efficient allocation rules are an example of a SCFs satisfying this property.

We can then prove there exists a tradeoff between inclusivity and total surplus extraction.

Corollary 2. *If F is fully extractive and inclusive, then it is not implementable in any WSC S .*

The result follows because inclusivity and complete extraction of surplus entail each type has an incentive to pretend the object is worth less to her than it actually is. This creates a tension with implementability in a WSC solution concept, which implies instead there exists at least one SCF in F providing each agent with the incentive not to misrepresent her type. This should be contrasted with the result in the previous example, which follows instead from the fact that the same SCF has to be simultaneously incentive compatible for all types of all agents as in the application above. The impossibility faced in this application is therefore harder to escape than the in the application in Section 6.1.

6.3 A Revenue Equivalence Theorem

Our results also allow us to extend Myerson's (1981) fundamental result about revenue equivalence of different auction formats to all SCFs that are fully implementable in a WSC solution concept.

As in Myerson (1981), let us assume that agents' values are drawn from set $[a_i, b_i] \subseteq \mathbb{R}_0^+$ according to a commonly known distribution, that agents are risk neutral, that their utility is additively separable in money and the value of the object, and that $v_i : T_i \rightarrow \mathbb{R}^+$ is non-negative, increasing, and differentiable in t_i for all $i \in I$ (this is the case, for example, if $v_i(t_i) = t_i$).

Let $\bar{q}_i^f(t_i)$ and $\bar{x}_i^f(t_i)$ denote respectively the average probability of winning and the average transfer for an agent of type t_i . An SCF $f = (q, x)$ is *differentiable* if both \bar{q}_i and \bar{x}_i are differentiable in t_i for all $i \in I$ almost everywhere, and two SCFs f and \tilde{f} are *assignment-equivalent* if $q^f = q^{\tilde{f}}$ almost everywhere. Notice that if f is ex-post efficient and agents' values are independently and identically distributed according to a cdf G , then \bar{q}^f is differentiable as $\bar{q}^f(t_i) = G^{n-1}(t_i)$. Moreover, if f and \tilde{f} are both ex-post efficient and the distribution of values atomless, f and \tilde{f} they are assignment-equivalent as the object always goes to the agent with the highest value and the probability of a tie is null.

Corollary 3. *If differentiable and assignment-equivalent SCFs f and \tilde{f} are fully implementable in WSC \mathcal{S} , then $\bar{x}_i^f(t_i) - \bar{x}_i^f(a_i) = \bar{x}_i^{\tilde{f}}(t_i) - \bar{x}_i^{\tilde{f}}(a_i)$ for all $i \in I$.*

Corollary 3 establishes a generalized version of the standard Revenue Equivalence Theorem of Myerson (1981), stating that the revenue of a given SCF f is determined by its allocation probability q up to an additive constant $\bar{x}^f(a_i)$. If we standardize the average payment of type a_i to 0, we obtain the familiar result that any two rules f and \tilde{f} that are fully implementable in SC \mathcal{S} (and their associated implementing mechanisms—for example, auctions) will yield the same ex-ante revenue to the planner unless they differ in the probability with which each type gets allocated the object.

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Appendix A Generalized Model

Non-standard Choice Correspondences

This section relaxes the assumption that agents best respond to their expectations, generalizing the results in the main body of the paper beyond the domain of von Neumann–Morgenstern preferences.

We can interpret the revelation principle as saying that some lotteries in the choice sets induced by an indirect implementing mechanism (but not in the direct one) can be safely neglected, as they are not going to be relevant. Formally, this requires that restricting the choice set of an agent of type t_i to the set of lotteries that would be a solution of the mechanism for some type $t'_i \in T_i$ does not affect her choice. This will require us to impose some form of Contraction Consistency, or Independence of Irrelevant Alternatives (see, for example, Property α of Sen (1971)). In the argument below, we only maintain the assumption that agents are consequentialist—that is, that their choices depend only on the set of alternatives they choose from.³⁰

As in Saran (2011) and Barlo and Dalkiran (2023), we model individual strategic decisions, for all $i \in I$, as choices over a set of *interim Anscombe-Aumann acts* (IAA acts) $x_i : T_{-i} \rightarrow \Delta(A)$. Denote as \mathcal{X} the set of all IAA acts. Notice that, for all i and t_i , $f(t_i, \cdot) \in \mathcal{X}$.

We can then define a choice correspondence C_{i,t_i} as mapping each non-empty subset X of \mathcal{X} to a subset of $\Delta(X)$. That is, for all $X \subseteq \mathcal{X}$, $C_{i,t_i}(X) \subseteq \Delta(X)$. As in Barlo and Dalkiran (2023) and unlike in Saran (2011), we do not assume C_{i,t_i} is generated by a menu-dependent preference order.

Notice that for any given $s_i \in \Delta(S_i)$ and $\sigma_{-i} \in \Sigma_{-i}$, the function $\mu(s_i, \sigma_{-i})$ is an IAA act. We can then denote the set of acts agent i of type t_i chooses from given her expectations

³⁰This rules out, for example, preferences for truth-telling.

as follows:

$$O_i(\sigma_{-i}) = \{x_i \in \mathcal{X} : x_i = \mu(s_i, \sigma_{-i}), s_i \in \Delta(S_i)\}$$

As in previous sections, we say $s_i \in \Delta(S_i)$ is a reply to σ_{-i} for type t_i whenever $s_i \in R_{i,t_i}(\sigma_{-i}) \subseteq \mu^{-1}(C_{i,t_i}(O_i(\sigma_{-i})))$. That is, the outcome of the actions chosen as a response to σ_{-i} is a subset of what agent i of type t_i would choose from the set of acts $O_i(\sigma_{-i})$. Notice that $\mu^{-1}(C_{i,t_i}(O_i(\sigma_{-i})))$ coincides with the set B_{i,t_i} considered in the main text in case the agent maximizes expected utility given σ_{-i} . We then say σ is a solution of a mechanism γ whenever there exists $e \in E(\gamma)$ such that $\sigma \in R(e)$.

Let O_i^{f,t_i} denote the set of IAA acts that agent i can generate in the direct mechanism (f, T) when her opponents truthfully report their type:

$$O_i^{f,t_i} = \{x_i \in \mathcal{X} : x_i \in f(t'_i, \iota_{-i}) \text{ where } t'_i \in T_i\}$$

Incentive Compatibility can then be generalized as in Saran (2011):

Definition 3 (Incentive Compatibility (IC)). *Let C_{i,t_i} be given. We say f satisfies IC for type $t_i \in T_i$ and $i \in I$ whenever $f(t_i, \cdot) \in C_{i,t_i}(O_i^{f,t_i})$. We say f is IC whenever it is IC for all $t_i \in T_i$ and $i \in I$.*

In other words, we require agents to choose the act associated with their type t_i when they expect their opponents to choose the acts associated with their types as well. In the case of BIC, this coincides with the set of acts maximizing expected utility in the choice set. To derive our main result for this section, we redefine WSC in terms of choice correspondences rather than utility maximization.

Definition 4 (Weak Choice Consistency (WCC)). *We say a solution concept \mathcal{S} satisfies WCC for a class of mechanisms $\tilde{\Gamma} \subseteq \Gamma$ whenever for all $\gamma \in \tilde{\Gamma}$, $i \in I$, $t_i \in T_i$ there exists $\sigma \in \mathcal{S}(\gamma)$ such that $\mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(X_i(\sigma_{-i}))$, where:*

$$X_i(\sigma_{-i}) = \{x_i \in \mathcal{X} : x_i = \mu(\sigma_i(t'_i), \sigma_{-i}) \text{ with } t'_i \in T_i\}.$$

We say \mathcal{S} satisfies WCC if it satisfies WCC for all $\gamma \in \Gamma$ such that $\mathcal{S}(\gamma) \neq \emptyset$.

It is immediately possible to extend Theorem 3 and, when F is a singleton, Theorem 1.

Theorem 6. *If F is implementable in WCC \mathcal{S} , then for all $i \in I$ and $t_i \in T_i$ there exists an $f^{i,t_i} \in F$ that is IC for i and t_i . Conversely, if F is implementable and there exists an $f^{i,t_i} \in F$ that is IC for i and t_i , then \mathcal{S} is WCC for $\Gamma^{F,\mathcal{S}}$.*

Notice that WCC implicitly assumes a mild form of contraction consistency between choices in $O_i(\sigma_{-i})$ and in $X_i(\sigma_{-i})$. In fact, if $\sigma \in \mathcal{S}(\gamma)$ is such that $\mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(O_i(\sigma_{-i}))$ and $X_i(\sigma_{-i}) \subseteq O_i(\sigma_{-i})$, WCC entails that $\mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(X_i(\sigma_{-i}))$.

This implicit assumption means it is not as easy to provide a sufficient condition for WCC as it was for WSC. Let us parallel the definition of SC and say \mathcal{S} is *Choice Consistent* (CC) for mechanism γ whenever for all $i \in I$ and $t_i \in T_i$ there exist $e, e' \in E(\gamma)$ and $\sigma \in R(e)$ such that $(\sigma_i, e_{i,t_i}) \in R(e')$. While this entails $\mu(\sigma_i(t_i), e_{i,t_i}) \in C_{i,t_i}(O_i(e_{i,t_i}))$, it is not enough to establish WCC as it does not preclude the possibility that $\mu(\sigma_i(t_i), e_{i,t_i}) \notin C_{i,t_i}(X_i(e_{i,t_i}))$. Without any form of contraction consistency, CC just implies that for all $i \in I$ and $t_i \in T_i$ there exists $f \in F$ and $\mathcal{O} \subseteq \mathcal{X}$ such that $O_i^{f,t_i} \subseteq \mathcal{O}$ and $f(t_i, \cdot) \in C_{i,t_i}(\mathcal{O})$. Using Barlo and Dalkiran's (2023) terminology, we can say f is *quasi-incentive compatible* (QIC) for agent i of type t_i .

Chernoff (1954) provides an example of a class of choice correspondences ruling out such a possibility without implying maximization of rational preferences (Sen, 1971). We say a choice correspondence C_{i,t_i} satisfies Independence of Irrelevant Alternatives (IIA) whenever for all $X, Y \subseteq \mathcal{X}$:

$$C_{i,t_i}(X) \subseteq Y \subseteq X \implies C_{i,t_i}(X) \subseteq C_{i,t_i}(Y).$$

By IIA, if $\mathcal{S}(\gamma)$ is CC then it is WCC as $\mu(\sigma_i(t_i), e_{i,t_i}) \in C_{i,t_i}(O_i(e_{i,t_i}))$ and:

$$C_{i,t_i}(O_i(e_{i,t_i})) \subseteq X_i(e_{i,t_i}) \subseteq O_i(e_{i,t_i}) \implies C_{i,t_i}(O_i(e_{i,t_i})) \subseteq C_{i,t_i}(X_i(e_{i,t_i})).$$

It is immediately possible to derive the following result by the same argument as in the main text.

Corollary 4. *If F is implementable in CC \mathcal{S} , then there exists an $f^{i,t_i} \in F$ that is QIC for type t_i and agent i . If, moreover, C_{i,t_i} satisfies IIA, f^{i,t_i} is IC for type t_i and agent i .*

These results allow us to extend the findings of de Clippel et al. (2019) and Kunimoto et al. (2023) about level- k and rationalizable implementation to all consequentialist choice correspondences.³¹ To this end, it is enough to tweak the definitions of the solution concepts in the main text by replacing the assumption $R \subseteq B$ with $R \subseteq \mu^{-1}(C_{i,t_i}(O_i(\sigma_{-i})))$. In particular, we can say IC is necessary for implementation in these solution concepts whenever C is IIA.

A limitation of this analysis is in the assumption that agents' choices depend only on the menu of acts they choose from. This assumption rules out, for instance, Quantal Response Equilibrium (McKelvey and Palfrey, 1995) and Sampling Equilibrium (Osborne and Rubinstein, 1998). In these models, agents' choices depend not only on the menu of available acts but on the number of times an act appears in the menu. We can accommodate these models by relaxing the assumption that, for all i and t_i , C_{i,t_i} 's domain is the set of all non-empty sets $X \subseteq \mathcal{A}$ and assume instead that C_{i,t_i} 's domain is the set of all non-empty bags with support in \mathcal{A} .³² We can get the same result as above (with slightly heavier notation) by adjusting the definitions of IC, QIC, WCC, CC, and IIA accordingly. In this case, both Sampling Equilibrium and Quantal Response Equilibrium can be considered as special cases of Behavioral Interim Equilibrium (Barlo and Dalkıran, 2023).

³¹Barlo and Dalkıran (2023) already extend BNE to non-rational choice correspondences with their Behavioral Interim Equilibrium (BIE) solution concept.

³²A bag, or multiset, is a generalization of the concept of set that allows more than one instance of each element. Its support is the set of elements that appear at least once.

Appendix B Proofs

Proof of Theorem 1. Suppose f is implementable in \mathcal{S} via mechanism $\gamma = (\mu, S)$, and suppose \mathcal{S} is WSC for γ . Then $\mathcal{S}(\gamma) \neq \emptyset$ and there exists $\sigma^{i,t_i} \in \mathcal{S}(\gamma)$ such that:

$$\int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t), t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t'_i, t_{-i}), t), t) dp_i(t_{-i}|t_i).$$

As $\sigma^{i,t_i} \in \mathcal{S}(\gamma)$, implementability of f yields $\mu(\sigma^{i,t_i}) = f$. Therefore, for $i \in I$ and $t_i, t'_i \in T_i$:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

As our choice of i, t_i , and t'_i was arbitrary, this is enough to establish that f is BIC.

Conversely, suppose f is BIC and implementable in \mathcal{S} via mechanism $\gamma = (\mu, S)$. Then, for all $t'_i \in T_i$ and $i \in I$:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f(t'_i, t_i), t) dp_i(t_{-i}|t_i).$$

As γ implements f , there exists $\sigma \in \mathcal{S}(\gamma)$ such that $\mu(\sigma) = f$ and thus:

$$\int_{T_{-i}} u_i(\mu(\sigma(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

Setting $\sigma^{i,t_i} = \sigma$ for all $i \in I$ and $t_i \in T_i$ concludes the proof. \square

Proof of Theorem 2. To prove we can strengthen the result of Theorem 1 to SIRBIC, we proceed by contradiction and suppose that, indeed, the incentive constraint holds with equality for some agent $i \in I$ and types $t_i, t'_i \in T_i$:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) = \int_{T_{-i}} u_i(f(t'_i, t_i), t) dp_i(t_{-i}|t_i).$$

As f is implementable in \mathcal{S} , there exists a solution σ of mechanism γ such that $\mu(\sigma) = f$.

Define $\tau : T \rightarrow \Sigma$ as agreeing with σ except that $\tau(t) = \sigma(t'_i, t_{-i})$ for all $t_{-i} \in T_{-i}$. As $\sigma \in \mathcal{S}(\gamma)$, there exist e such that $\sigma \in B(e)$. Given τ yields the same expected utility as σ conditional on expectations e , $\sigma \in B(e)$ implies $\tau \in B(e)$. Then by the definition of implementation above, for all $t_{-i} \in T_{-i}$:

$$f(t_i, t_{-i}) = \mu(\tau(t)) = \mu(\sigma(t'_i, t_{-i})) = f(t'_i, t_{-i}).$$

This concludes the proof. □

Proof of Theorem 3. Suppose F is implementable in WSC \mathcal{S} via mechanism $\gamma = (\mu, S)$ with $\mathcal{S}(\gamma) \neq \emptyset$. Then for each $i \in I$ and $t_i \in T_i$, there exists $\sigma^{i,t_i} \in \mathcal{S}(\gamma)$ such that for all $t'_i \in T_i$:

$$\int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t), t)) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma^{i,t_i}(t'_i, t_{-i}), t)) dp_i(t_{-i}|t_i).$$

As $\sigma^{i,t_i} \in \mathcal{S}(\gamma)$, implementability of F yields $\mu(\sigma^{i,t_i}) = f^{i,t_i}$ for some $f^{i,t_i} \in F$. Therefore, for all $t'_i \in T_i$:

$$\int_{T_{-i}} u_i(f^{i,t_i}(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f^{i,t_i}(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

This is enough to prove f^{i,t_i} is BIC for agent i and type t_i .

As for the converse, suppose F is implementable in \mathcal{S} via mechanism γ and suppose that for all $i \in I$ and $t_i \in T_i$ there exists an $f^{i,t_i} \in F$ that is BIC for agent i and type t_i . Then for each such f^{i,t_i} , i , and t_i there exists a solution σ^{i,t_i} such that $f^{i,t_i} = \mu(\sigma^{i,t_i})$. A simple substitution in the BIC inequality then yields that WSC holds. □

Proof of Theorem 4. If F is implementable in \mathcal{S} , then any $f \in F$ is such that $f = \mu(\sigma)$ for $\sigma \in \mathcal{S}$. As \mathcal{S} is TWSC, it is immediate that f is BIC from the definition of TWSC by substituting $f = \mu(\sigma)$. Conversely, suppose F is implementable in \mathcal{S} . As any $\sigma \in \mathcal{S}$ is such that $\mu(\sigma) \in F$, TWSC follows immediately from the fact that all functions $f \in F$ are BIC. □

Proof of Theorem 5. Suppose F is implementable in SC \mathcal{S} , and suppose E is type-independent. By SC, for all $i \in I$ there exists $e \in E(\gamma)$ and $\sigma \in R(e)$ such that $(\sigma_i, e_i) \in \mathcal{S}(\gamma)$. Then for all $t'_i \in T_i$, by $\sigma \in R(e) \subseteq B(e)$ it is true that:

$$\int_{T_{-i}} u_i(\mu(\sigma_i(t_i), e_i(t_{-i})), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(\mu(\sigma_i(t'_i), e_i(t_{-i})), t) dp_i(t_{-i}|t_i).$$

For each $i \in I$, let $f = \mu \circ (\sigma_i, e_i)$. By SC, $\mu \circ (\sigma_i, e_i) \in F$, so $f \in F$. Moreover:

$$\int_{T_{-i}} u_i(f(t), t) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} u_i(f(t'_i, t_{-i}), t) dp_i(t_{-i}|t_i).$$

This entails that f is BIC for all types of agent i . This concludes the proof. \square

Proof of Corollary 2. We now show that supposing F is implementable in WSC \mathcal{S} leads to a contradiction. Consider any agent $i \in I$. By inclusivity, for each $f \in F$ there exist types $t_i, t'_i \in T_i$ such that $q_i^f(t'_i, t_{-i}) > 0$ and $t_i > t'_i$ for some profile t_{-i} . By WSC and Theorem 3, we then know that if F is implementable in \mathcal{S} , for all $i \in I$ and $t_i \in T_i$, then there exists an $f \in F$ that is BIC for i and t_i . Therefore, for all $i \in I$, $t_i \in T_i$ and $t'_i < t_i$, full surplus extraction implies:

$$0 = \int_{T_{-i}} (q_i^f(t)v_i(t) - q_i^f(t'_i)v_i(t)) dp_i(t_{-i}|t_i) \geq \int_{T_{-i}} q_i^f(t'_i, t_{-i})(v_i(t) - v_i(t'_i, t_{-i})) dp_i(t_{-i}|t_i)$$

As v_i is strictly increasing in i 's type and F is inclusive:

$$\int_{T_{-i}} q_i^f(t'_i, t_{-i})(v_i(t) - v_i(t'_i, t_{-i})) dp_i(t_{-i}|t_i) > 0.$$

This inequality contradicts the fact that f is BIC for i and t_i , concluding the proof. \square

Proof of Corollary 3. As f is implementable in \mathcal{S} WSC, it is BIC. So $t_i^* = t_i$ must maximize the payoff function $\bar{q}^f(t_i^*)v_i(t_i) - \bar{x}_i^f(t_i^*)$. A necessary condition for a maximum is that the first derivative with respect to v_i of this function is null at t_i —that is, $\frac{\partial \bar{x}_i^f(t_i)}{\partial t_i} = \frac{\partial \bar{q}^f(t_i)}{\partial t_i} v_i(t_i)$.

Then:

$$\bar{x}(t_i) - \bar{x}(a_i) = \int_{a_i}^{t_i} v_i(t'_i) \frac{\partial \bar{q}^f(t'_i)}{\partial t_i} dt'_i.$$

Analogous reasoning for \tilde{f} and assignment-equivalence yield $\bar{x}^f(t_i) - \bar{x}^f(a_i) = \bar{x}^{\tilde{f}}(t_i) - \bar{x}^{\tilde{f}}(a_i)$, concluding the proof. \square

Proof of Theorem 6. Suppose F is implementable in WCC \mathcal{S} via mechanism $\gamma = (\mu, S)$ with $\mathcal{S}(\gamma) \neq \emptyset$. Then for each $i \in I$ and $t_i \in T_i$ there exists $\sigma \in \mathcal{S}(\gamma)$ such that $\mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(X_i(\sigma_{-i}))$, where:

$$X_i(\sigma_{-i}) = \{x_i \in \mathcal{X} : x_i = \mu(\sigma_i(t'_i), \sigma_{-i}) \text{ with } t'_i \in T_i\}.$$

As $\sigma \in \mathcal{S}(\gamma)$, implementability of F yields $\mu(\sigma) = f$ for some $f \in F$. Then:

$$X_i(\sigma_{-i}) = \{x_i \in \mathcal{X} : x_i = \mu(\sigma_i(t'_i), \sigma_{-i}) = f(t'_i, \cdot), t'_i \in T_i\} = O_i^{f,t_i}.$$

Then $f(t_i, \cdot) = \mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(X_i(\sigma_{-i})) = C_{i,t_i}(O_i^{f,t_i})$, which is enough to prove $f \in F$ is BIC for agent i and type t_i .

As for the converse, suppose F is implementable in \mathcal{S} via mechanism γ and suppose that for each $i \in I$ and $t_i \in T_i$ there exists an $f \in F$ that is IC for agent i and type t_i . As f is IC for i and t_i , $f(t_i, \cdot) \in C_{i,t_i}(O_i^{f,t_i})$. Moreover, as F is implementable, there exists a solution $\sigma \in \mathcal{S}(\gamma)$ such that $f = \mu(\sigma)$. Then:

$$O_i^{f,t_i} = \{x_i \in \mathcal{X} : x_i = f(t'_i, \cdot) = \mu(\sigma_i(t'_i), \sigma_{-i}) \text{ with } t'_i \in T_i\} = X_i(\sigma_{-i}).$$

This entails that for each i and t_i there exists $\sigma \in \mathcal{S}(\gamma)$ such that $\mu(\sigma_i(t_i), \sigma_{-i}) \in C_{i,t_i}(X_i(\sigma_{-i}))$.

As our initial choice of i and t_i was arbitrary, this concludes the proof. \square