

# Uhlig's Toolkit

SFU

$$Y = C + I$$

$$Y = C + S$$

$$C + I = C + S$$

$$I = S$$

$$K_t = (1 - \delta)K_{t-1} + I_t$$

$$\text{Max } U(x, y)$$

s.t.

$$x P_x + y P_y = M$$

$$\frac{U'_x}{U'_y} = \frac{P_x}{P_y}$$

مقدارهای حاشیه

مقدارهای حاشیه

$$P_t C_t + P_t I_t + P_t T_t + B_t + M_t = P_t w_t L_t + r_t K_{t-1} P_t + (1 + i_{t-1}) B_{t-1} + M_{t-1} + P_t D_t$$

مقدارهای دولت

$$P_t G_t + (1 + i_{t-1}) B_{t-1} = P_t T_t + M_t - M_{t-1} + B_t$$

$$P_t C_t + P_t I_t + P_t G_t = P_t w_t L_t + r_t P_t K_{t-1} + P_t D_t$$

$$C_t + I_t + G_t = w_t L_t + r_t K_{t-1} + D_t$$

$$Y_t = w_t L_t + r_t K_{t-1} + D_t = F(K_{t-1}, L_t)$$

$$Y_t = C_t + I_t + G_t$$

$$K_t = (1 - \delta) K_{t-1} + I_t$$

طبقه بندی متغیرها:

$$y_t = \alpha + \beta x_t + \varepsilon_t$$

$$y_t = \hat{\alpha} + \hat{\beta} x_t + e_t$$

$$y(t)$$

$$E(\varepsilon_t) = 0$$

متغیرهای تصادفی در مقطعی:

متغیرهای درونی یا همبستگی:

$$y_t = \alpha + \beta x_t + \varepsilon_t$$

Control and state variables: متغیرهای کنترل و وضعیت

حالتی که در طول زمان تغییر وضعیت می کند

$$y_t = \alpha + \beta y_{t-1} + \varepsilon_t \quad \text{معادله تفاضلی مرتبه اول (AR(1))}$$

$$y = a + bx + cx^2$$

AR(1) Auto Regression: خودرگرسیون

روش حل معادله تفاضلی مرتبه اول:

$$y_t = \alpha + \beta y_{t-1} + \varepsilon_t, \quad E(\varepsilon_t) = 0$$

① روش جدایی

$$y_{t-1} = \alpha + \beta y_{t-2} + \varepsilon_{t-1}$$

② روش تکرار

$$y_t = \alpha + \beta y_{t-1} + \varepsilon_t, \quad E(\varepsilon_t) = 0 \quad \text{① ارزش صاف$$

$$y_{t+1} = \alpha + \beta y_{t+2} + \varepsilon_{t+1} \quad \text{② ارزش عملی رفقه}$$

$$\text{③ بهای نامعین}$$

$$y_t = \alpha + \beta (\alpha + \beta y_{t-2} + \varepsilon_{t-1}) + \varepsilon_t$$

$$y_t = \alpha + \alpha\beta + \beta^2 y_{t-2} + \varepsilon_t + \beta \varepsilon_{t-1}$$

$$y_{t-2} = \alpha + \beta y_{t-3} + \varepsilon_{t-2}$$

$$y_t = \underbrace{\alpha + \alpha\beta + \alpha\beta^2 + \dots + \alpha\beta^t}_{\text{باقی}} + \underbrace{\beta^{t+1} y_{-1}}_{\text{تقراریه}} + \underbrace{\varepsilon_t + \beta \varepsilon_{t-1} + \dots + \beta^t \varepsilon_0}_{\text{تاریخچه در حال گذشته}}$$

$$E(y_t) = \alpha [1 + \beta + \beta^2 + \dots + \beta^t] + \beta^{t+1} y_{-1}$$

$$E(y_t) = \alpha \frac{[1 - \beta^{t+1}]}{1 - \beta} + \beta^{t+1} y_{-1}$$

$$\beta \begin{cases} < 1 \\ = 1 \\ > 1 \end{cases}$$

if  $\beta < 1$

$$\lim_{t \rightarrow \infty} E(y_t) = \lim_{t \rightarrow \infty} \frac{\alpha [1 - \beta^{t+1}]}{1 - \beta} + \lim_{t \rightarrow \infty} \beta^{t+1} y_{-1}$$

$$= \frac{\alpha}{1 - \beta} + 0$$

$$E(y_t) = \frac{\alpha}{1 - \beta}$$

Steady State:

$$x_t = x_{t-1} = E_t x_{t+1} = \bar{x}$$

$$y_t = \alpha + \beta y_{t-1} + \varepsilon_t$$

$$\bar{y} = \alpha + \beta \bar{y} + \bar{\varepsilon} \rightarrow 0$$

$$(1 - \beta) \bar{y} = \alpha$$

$$\bar{y} = \frac{\alpha}{1 - \beta}$$

$\beta < 1$

$$y_t = \alpha [1 + \beta + \beta^2 + \dots + \beta^t] + \beta^{t+1} y_{-1} + \varepsilon_t + \beta \varepsilon_{t-1} + \dots + \beta^t \varepsilon_0$$

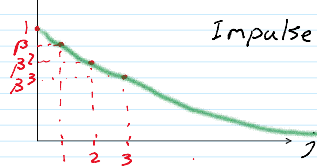
$$y_t = \frac{\alpha}{1 - \beta} + \varepsilon_t + \beta \varepsilon_{t-1} + \beta^2 \varepsilon_{t-2} + \dots$$

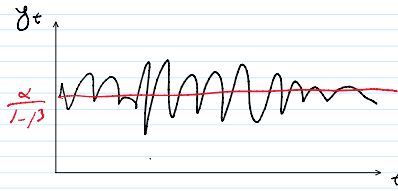
$$\frac{\partial y_t}{\partial \varepsilon_{t-j}} = \frac{\partial y_{t+j}}{\partial \varepsilon_t} = \beta^j \quad j \in [0, \infty)$$

Impulse Response

$$\frac{\partial y_{t+j}}{\partial \varepsilon_t}$$

Impulse Response Function





$\beta=1$

$$\bar{\delta} = \frac{\alpha}{1-\beta} = \frac{\alpha}{1-1} = \frac{\alpha}{0} = \infty \quad 1-\beta=0 \quad \text{no limit}$$

$$y_t = \alpha [1 + \beta + \beta^2 + \dots + \beta^t] + \beta^{t+1} y_{-1} + \varepsilon_t + \beta \varepsilon_{t-1} + \dots + \beta^t \varepsilon_0$$

$$y_t = \alpha [1 + 1 + 1 + \dots + 1] + y_{-1} + \varepsilon_t + \varepsilon_{t-1} + \dots + \varepsilon_0$$

$$y_t = \alpha (t+1) + y_{-1} + \varepsilon_t + \varepsilon_{t-1} + \dots + \varepsilon_0$$

$$E(y_t) = \alpha (t+1) + y_{-1}$$

li  $E(y_t) = \infty$

$t \rightarrow \infty$



$\beta > 1$

$$\frac{1}{\beta} \delta_t = \frac{\alpha}{\beta} + \frac{\beta \delta_{t-1}}{\beta} + \frac{\varepsilon_t}{\beta}$$

$$\frac{1}{\beta} \delta_t = \frac{\alpha}{\beta} + \delta_{t-1} + \frac{1}{\beta} \varepsilon_t$$

$$\delta_{t-1} = \frac{\alpha}{\beta} + \frac{1}{\beta} \delta_t - \frac{1}{\beta} \varepsilon_t$$

$$\delta_t = -\frac{\alpha}{\beta} + \frac{1}{\beta} \delta_{t+1} - \frac{1}{\beta} \varepsilon_{t+1}$$

$$\delta_t = -\frac{\alpha}{\beta} + \frac{1}{\beta} \left[ -\frac{\alpha}{\beta} + \frac{1}{\beta} \delta_{t+2} - \frac{1}{\beta} \varepsilon_{t+2} \right] - \frac{1}{\beta} \varepsilon_{t+1}$$

$$\delta_t = -\frac{\alpha}{\beta} \left[ 1 + \frac{1}{\beta} + \frac{1}{\beta^2} + \dots \right] + \frac{1}{\beta^t} \delta_{2t} - \frac{1}{\beta} \left[ \varepsilon_{t+1} + \frac{1}{\beta} \varepsilon_{t+2} + \dots \right]$$

$$\beta > 1 \Rightarrow \frac{1}{\beta} < 1$$

$$\delta_t = \frac{-\frac{\alpha}{\beta}}{1 - \frac{1}{\beta}} - \frac{1}{\beta} \left[ \varepsilon_{t+1} + \frac{1}{\beta} \varepsilon_{t+2} + \dots \right]$$

$$\delta_t = \frac{\alpha}{1-\beta} - \frac{1}{\beta} \left[ \varepsilon_{t+1} + \frac{1}{\beta} \varepsilon_{t+2} + \dots \right]$$

$$E y_t = \frac{\alpha}{1-\beta}$$

$$r_t = \beta E_t r_{t+1} + \beta x_t$$

مختار

$0 < \beta < 1$

مختار (رأبيل) مختار (رأبيل) مختار

Predetermined and non-predetermined variables



TFP: Total Factor Productivity

$$\log Z_t = (1-\psi) \log \bar{Z} + \psi \log Z_{t-1} + \varepsilon_t, \quad \varepsilon_t \sim \text{i.i.d. } N(0, \sigma^2)$$

$$Z_{t-1} = Z_t = E_t Z_{t+1} = \bar{Z}, \quad \bar{\varepsilon} = E(\varepsilon_t) = 0$$

$$0 < \psi < 1$$

$$\log \bar{Z} = 0 \Rightarrow \bar{Z} = 1$$

$$\max_{C_t, N_t, K_t} \sum_{t=0}^{\infty} \beta^t \left[ \frac{C_t^{1-\eta}}{1-\eta} \right]$$

s.t.

$$C_t + K_t = Z_t K_{t-1}^\beta N_t^{1-\beta} + (1-\delta)K_{t-1}, \quad N_t = 1$$

$$\log Z_t = (1-\psi) \log \bar{Z} + \psi \log Z_{t-1} + \varepsilon_t$$

$$K_{-1} = Z_0$$

$$\varepsilon_t \sim \text{i.i.d. } N(0, \sigma^2)$$

$$L = E_t \sum_{t=0}^{\infty} \beta^t \left[ \frac{C_t^{1-\eta}}{1-\eta} + \lambda_t \left[ Z_t K_{t+1}^\beta + (1-\delta)K_{t+1} - C_t - K_t \right] \right]$$

$$\frac{\partial L}{\partial C_t} = \beta^t \left[ C_t^{-\eta} - \lambda_t \right] = 0 \quad (1) \quad \lambda_t = C_t^{-\eta}$$

$$\frac{\partial L}{\partial \lambda_t} = \beta^t \left[ Z_t K_{t+1}^\beta + (1-\delta)K_{t+1} - C_t - K_t \right] = 0 \quad (2)$$

$$\frac{\partial L}{\partial K_t} = -\beta^t \lambda_t + \beta^{t+1} E_t \left[ \lambda_{t+1} \left( \beta Z_{t+1} K_t^{\beta-1} + (1-\delta) \right) \right] = 0 \quad (3)$$

(1), (3)

$$C_t^{-\eta} = \beta E_t C_{t+1}^{-\eta} \left[ \beta Z_{t+1} K_t^{\beta-1} + (1-\delta) \right]$$

$$(1) \quad \frac{C_t^{-\eta}}{\lambda_t} = 1$$

$$C_t^{-\eta} = \beta E_t C_{t+1}^{-\eta} \left[ \beta Z_{t+1} K_t^{\beta-1} + (1-\delta) \right]$$

$$\frac{C_t^{-\eta}}{\beta E_t C_{t+1}^{-\eta}} = E_t \left[ \beta Z_{t+1} K_t^{\beta-1} + (1-\delta) \right]$$

$$\frac{C_t^{-\eta}}{\beta E_t C_{t+1}^{-\eta}} = \underbrace{\left[ \beta Z_{t+1} K_t^{\beta-1} + (1-\delta) \right]}_{R_t}$$

$$\frac{C_t^{-\eta}}{\beta E_t C_{t+1}^{-\eta}} = \overbrace{[r_t + 1 - \delta]}$$

$$r_t = E_t [\beta z_{t+1} k_t^{\beta-1}] + 1 - \delta$$

$$\left( \frac{C_t}{E_t C_{t+1}} \right)^{-\eta} = \beta R_t$$

$$\frac{C_t}{E_t C_{t+1}} = (\beta R_t)^{-\frac{1}{\eta}}$$

EPSTEIN - ZIL PREFERENCE

$$\lim_{T \rightarrow \infty} E_0 [\beta^T C_T^{-\eta} K_T] = 0$$

Transversality Condition

$$\textcircled{1} \quad 1 = E_t \left[ \beta \left( \frac{C_t}{C_{t+1}} \right)^{\eta} R_{t+1} \right]$$

$$\textcircled{2} \quad C_t = z_t k_{t-1}^{\beta} + (1 - \delta) k_{t-1} - k_t$$

$$\textcircled{3} \quad R_t = \beta z_t k_{t-1}^{\beta-1} + (1 - \delta)$$

$$\textcircled{4} \quad \log z_t = (1 - \psi) \log \bar{z} + \psi \log z_{t-1} + \varepsilon_t$$

$$x_t = x_{t-1} = E_t x_{t+1} = \bar{x}$$

Steady State:

$$\textcircled{1} \quad 1 = \beta \left( \frac{\bar{z}}{\bar{z}} \right)^{\eta} \bar{R} \Rightarrow \bar{R} = \frac{1}{\beta}$$

$$\textcircled{2} \quad \bar{c} = \bar{z} \bar{k}^{\beta} + (1 - \delta) \bar{k} - \bar{k}$$

$$\textcircled{3} \quad \bar{R} = \beta \bar{z} \bar{k}^{\beta-1} + (1 - \delta)$$

$$\textcircled{4} \quad \bar{z} = 1$$

معادلات را از معلوم ترین به مجهول ترین بازنویس می کنیم

$$\textcircled{1} \quad \bar{z} = 1$$

$$\beta = \frac{1}{1+\rho} = \frac{1}{1+r}$$

$$\bar{F} = \rho$$

$$\textcircled{2} \quad \bar{R} = \frac{1}{\beta}$$

$$\textcircled{3} \quad \bar{K} = \left( \frac{\rho \bar{Z}}{\bar{R} - 1 + \delta} \right)^{\frac{1}{1-\rho}}$$

$$\textcircled{4} \quad \bar{Y} = \bar{Z} \bar{K}^{\rho}$$

$$\textcircled{5} \quad \bar{C} = \bar{Y} - \delta \bar{K} \Rightarrow \bar{Y} = \bar{C} + \delta \bar{K}$$

The competitive Equilibrium:

$$\max_{C, K_t} E \left[ \sum_{t=0}^{\infty} \beta^t \frac{C_t^{1-\eta}}{1-\eta} \right]$$

s.t.

$$C_t + \bar{I}_t = W_t N_t^s + r_t K_{t-1}^s$$

$$N_t^s = 1$$

$$K_t^s = (1-\delta) K_{t-1}^s + \bar{I}_t$$

$$\max_{N_t, K_{t-1}} \Pi_t = Z_t K_{t-1}^{\rho} N_t^{1-\rho} - W_t N_t^d - r_t K_{t-1}^d$$

$$N_t^s = N_t^d = N_t = 1$$

$$K_{t-1}^s = K_{t-1}^d = K_{t-1}$$

$$\checkmark C_t + K_t = Z_t K_{t-1}^{\rho} + (1-\delta) K_{t-1}$$

$$\begin{cases} Y_t = C_t + \bar{I}_t \\ Y_t = Z_t K_{t-1}^{\rho} \\ K_t = (1-\delta) K_{t-1} + \bar{I}_t \end{cases}$$

$$\frac{\partial \Pi_t}{\partial N_t} = (1-\rho) Z_t K_{t-1}^{\rho} N_t^{-\rho} - W_t = 0$$

$$\frac{\partial \Pi_t}{\partial K_{t-1}} = \rho Z_t K_{t-1}^{\rho-1} N_t^{1-\rho} - r_t = 0$$

$$W_t = MPN_t = \frac{(1-\rho) Y_t}{N_t} = (1-\rho) \frac{Z_t K_{t-1}^{\rho} N_t^{1-\rho}}{N_t}$$

$$r_t = MPK_t = \rho \frac{Y_t}{K_t} = \rho \frac{Z_t K_{t-1}^{\rho} N_t^{1-\rho}}{K_t}$$

$$r_t = MPK_t = \beta \frac{Y_t}{K_{t+1}} = \beta \frac{z_t K_{t-1}^\alpha N_t^{1-\alpha}}{K_{t+1}}$$

$$\textcircled{1} \frac{\partial L}{\partial \lambda_t} = w_t + r_t K_{t-1} + (1-\delta) - c_t - k_t = 0$$

$$\textcircled{2} \frac{\partial L}{\partial c_t} = c_t^{-\beta} - \lambda_t = 0$$

$$\textcircled{3} \frac{\partial L}{\partial K_t} = -\lambda_t + \beta E_t \lambda_{t+1} [r_t + (1-\delta)] = 0$$

$$X_t = A X_{t-1} + \varepsilon_t$$

$$\hat{x}_t = \frac{X_t - X_{t-1}}{X_{t-1}}$$

$$\hat{x}_t \approx \ln X_t - \ln X_{t-1} = \ln \frac{X_t}{X_{t-1}}$$

نرخ رشد - خصی کردن بدل عمل و ضمیمه میباید:

$$X_t = X_{t-1} = E_t X_{t+1} = \bar{X}$$

$$\textcircled{1} \hat{x}_t = \ln X_t - \ln \bar{X}$$

$$\hat{x}_t = \ln \frac{X_t}{\bar{X}}$$

$$\hat{x}_t = \frac{X_t - \bar{X}}{\bar{X}} = \frac{X_t}{\bar{X}} - 1 = \hat{x}_t$$

$$\frac{X_t}{\bar{X}} = 1 + \hat{x}_t$$

$$\textcircled{2} \left. \begin{aligned} X_t &= \bar{X} (1 + \hat{x}_t) \\ Y_t &= \bar{Y} (1 + \hat{y}_t) \end{aligned} \right\} \hat{x}_t \hat{y}_t \approx 0$$

$$\textcircled{1} \hat{x}_t = \ln \frac{X_t}{\bar{X}} \Rightarrow \frac{X_t}{\bar{X}} = e^{\hat{x}_t}$$

$$\textcircled{3} X_t = \bar{X} e^{\hat{x}_t}$$

$$\begin{aligned} Y_t &= \bar{z}_t K_{t-1}^\alpha N_t^{1-\alpha} \\ \bar{Y} &= \bar{z} \bar{K}^\alpha \bar{N}^{1-\alpha} \end{aligned}$$

$$\ln Y_t = \ln \bar{z}_t + \alpha \ln K_{t-1} + (1-\alpha) \ln N_t$$

$$\ln \bar{Y} = \ln \bar{z} + \alpha \ln \bar{K} + (1-\alpha) \ln \bar{N}$$

$$1 - \alpha \ln \bar{N} = \ln \bar{z} + \alpha (\ln K_{t-1} - \ln \bar{K}) + (1-\alpha) \ln \bar{N}$$



$$\ln \bar{Y} = \ln \bar{Z} + \alpha \ln \bar{K} + (1-\alpha) \ln \bar{N}$$

$$\ln Y_t - \ln \bar{Y} = \ln Z_t - \ln \bar{Z} + \alpha (\ln K_{t-1} - \ln \bar{K}) + (1-\alpha) (\ln N_t - \ln \bar{N})$$

$$\hat{y}_t = \hat{z}_t + \alpha \hat{k}_{t-1} + (1-\alpha) \hat{n}_t$$

$$Y_t = C_t + I_t$$

$$\bar{Y} = \bar{C} + \bar{I} \Rightarrow \frac{\bar{C}}{\bar{Y}} + \frac{\bar{I}}{\bar{Y}} = 1$$

$$\bar{Y} (1 + \hat{y}_t) = \bar{C} (1 + \hat{c}_t) + \bar{I} (1 + \hat{i}_t)$$

$$\cancel{\bar{Y}} + \bar{Y} \hat{y}_t = \cancel{\bar{C}} + \bar{C} \hat{c}_t + \cancel{\bar{I}} + \bar{I} \hat{i}_t$$

$$\hat{y}_t = \frac{\bar{C}}{\bar{Y}} \hat{c}_t + \frac{\bar{I}}{\bar{Y}} \hat{i}_t$$

$$Y_t = a + X_t, \quad \bar{Y} = a + \bar{X}$$

$$\bar{Y} (1 + \hat{y}_t) = a + \bar{X} (1 + \hat{x}_t)$$

$$\cancel{\bar{Y}} + \bar{Y} \hat{y}_t = \cancel{a} + \cancel{\bar{X}} + \bar{X} \hat{x}_t$$

$$\bar{Y} \hat{y}_t = \bar{X} \hat{x}_t$$

$$\hat{y}_t = \frac{\bar{X}}{\bar{Y}} \hat{x}_t$$

$$X_t + a = (1-b) \frac{Y_t}{Z_t}$$

$$\bar{X} + a = (1-b) \frac{\bar{Y}}{\bar{Z}}$$

$$\ln(X_t + a) = \ln(1-b) + \ln Y_t - \ln Z_t$$

$$\widehat{(X_t + a)} = \hat{y}_t - \hat{z}_t$$

$$\widehat{X_t + a} = \frac{X_t + a - (\bar{X} + a)}{\bar{X} + a} = \frac{X_t - \bar{X}}{\bar{X} + a} \times \frac{\bar{X}}{\bar{X}}$$

$$\widehat{X_t + a} = \frac{\bar{X}}{\bar{X} + a} \underbrace{\left( \frac{X_t - \bar{X}}{\bar{X}} \right)}_{\hat{x}_t} = \frac{\bar{X}}{\bar{X} + a} \hat{x}_t = \hat{y}_t - \hat{z}_t$$

$$\textcircled{1} \quad 1 = \beta E_t \left( \frac{C_{t+1}}{C_t} \right)^{-\eta} R_{t+1}$$

$$1 = \beta \left( \frac{\bar{C}}{\bar{C}} \right)^{-\eta} \bar{R}$$

$$a = \eta [C_t - E_t C_{t+1}] + \hat{r}_{t+1}$$

$$\textcircled{2} \quad C_t = \underbrace{z_t k_{t-1}^{\beta}}_{y_t} + (1-\delta)k_{t-1} - k_t$$

$$Y_t = z_t k_{t-1}^{\beta} \quad \hat{k}_{t-1} = \ln k_{t-1} - \ln \bar{k}$$

$$\hat{y}_t = \hat{z}_t + \beta \hat{k}_{t-1}$$

$$\bar{c} = \bar{y} + (1-\delta)\bar{k} - \bar{k}$$

$$\bar{c} (\cancel{1} + \hat{c}_t) = \bar{y} (\cancel{1} + \hat{y}_t) + (1-\delta)\bar{k} (\cancel{1} + \hat{k}_{t-1}) - \bar{k} (\cancel{1} + \hat{k}_t)$$

$$\hat{c}_t = \frac{\bar{y}}{\bar{c}} \hat{y}_t + \frac{(1-\delta)\bar{k}}{\bar{c}} \hat{k}_{t-1} - \frac{\bar{k}}{\bar{c}} \hat{k}_t$$

$$\hat{c}_t = \frac{\bar{y}}{\bar{c}} (\hat{z}_t + \beta \hat{k}_{t-1}) + \frac{(1-\delta)\bar{k}}{\bar{c}} \hat{k}_{t-1} - \frac{\bar{k}}{\bar{c}} \hat{k}_t$$

$$\textcircled{3} \quad R_t = \beta z_t k_{t-1}^{\beta-1} + (1-\delta)$$

$$\bar{r} (\cancel{1} + \hat{r}_t) = \beta \bar{z} \bar{k}^{\beta-1} (\cancel{1} + \hat{z}_t + (\beta-1)\hat{k}_{t-1}) + (1-\delta)$$

$$\bar{r} \hat{r}_t = \beta \bar{z} \bar{k}^{\beta-1} (\hat{z}_t + (\beta-1)\hat{k}_{t-1})$$

$$\hat{r}_t = \frac{\beta \bar{z} \bar{k}^{\beta-1}}{\bar{r}} (\hat{z}_t + (\beta-1)\hat{k}_{t-1})$$

$$\hat{r}_t = (1-\beta(1-\delta)) (\hat{z}_t - (1-\beta)\hat{k}_{t-1})$$

$$\textcircled{4} \quad \hat{z}_t = \psi \hat{z}_{t-1} + \varepsilon_t$$

$$\textcircled{1} \quad a = E_t [\eta (\hat{c}_t - \hat{c}_{t+1}) + \hat{r}_{t+1}]$$

$$\textcircled{2} \quad \hat{c}_t = \frac{\bar{y}}{\bar{c}} \hat{z}_t + \frac{\bar{k}}{\beta \bar{c}} \hat{k}_{t-1} - \frac{\bar{k}}{\bar{c}} \hat{k}_t$$

$$\textcircled{3} \quad \hat{r}_t = (1-\beta(1-\delta)) (\hat{z}_t - (1-\beta)\hat{k}_{t-1})$$

$$\textcircled{4} \quad \hat{z}_t = \psi \hat{z}_{t-1} + \varepsilon_t$$

من سیم معادلات بارزین فرایب تعیین:

$$\rightarrow \hat{k}_t = v_{kk} \hat{k}_{t-1} + v_{kz} \hat{z}_t$$

$$\hat{r}_t = v_{rk} \hat{k}_{t-1} + v_{rz} \hat{z}_t$$

$$\hat{c}_t = v_{ck} \hat{k}_{t-1} + v_{cz} \hat{z}_t$$

$$E \hat{z}_{t+1} = \psi \hat{z}_t$$

$$\textcircled{2} \quad \hat{c}_t = (1 + \delta \frac{\bar{K}}{C}) \hat{z}_t + \frac{\bar{K}}{\beta C} \hat{k}_{t-1} - \frac{\bar{K}}{C} \hat{k}_t$$

$$\hat{c}_t = v_{ck} \hat{k}_{t-1} + v_{cz} \hat{z}_t = (1 + \delta \frac{\bar{K}}{C}) \hat{z}_t + \frac{\bar{K}}{\beta C} \hat{k}_{t-1} - \frac{\bar{K}}{C} (v_{kk} \hat{k}_{t-1} + v_{kz} \hat{z}_t)$$

$$v_{cz} = \frac{\gamma}{C} - \frac{\bar{K}}{C} v_{kz}$$

$$v_{ck} = (\frac{1}{\beta} - v_{kk}) v_{kz}$$

$$\textcircled{3} \quad \hat{r}_t = (1 - \beta(1 - \delta)) (\hat{z}_t - (1 - \beta) \hat{k}_{t+1}) = v_{rk} \hat{k}_{t+1} + v_{rz} \hat{z}_t$$

$$v_{rk} = -(1 - \beta)(1 - \beta(1 - \delta))$$

$$v_{rz} = 1 - \beta(1 - \delta)$$

$$\textcircled{1} \quad 0 = E_t [\eta (\hat{c}_t - \hat{c}_{t+1}) + \hat{r}_{t+1}]$$

$$0 = E_t [\eta (v_{ck} \hat{k}_{t+1} + v_{cz} \hat{z}_t) - (v_{ck} \hat{k}_t + v_{cz} \hat{z}_{t+1}) + (v_{rk} \hat{k}_t + v_{rz} \hat{z}_{t+1})]$$

$$= (v_{rk} - \eta v_{ck}) \hat{k}_t + \eta v_{ck} \hat{k}_{t+1} + ((v_{rz} - \eta v_{cz}) \psi + v_{cz}) \hat{z}_t$$

$$= ((v_{rk} - \eta v_{ck}) v_{kk} + \eta v_{ck}) \hat{k}_{t-1}$$

$$+ ((v_{rk} - \eta v_{ck}) v_{kz} + (v_{rz} - \eta v_{cz}) \psi + \eta v_{cz}) \hat{z}_t$$

$$(v_{rk} - \eta v_{ck}) v_{kk} + \eta v_{ck} = 0$$

$$(v_{rk} - \eta v_{ck}) v_{kz} + (v_{rz} - \eta v_{cz}) \psi + \eta v_{cz} = 0$$

$$0 = (-(1 - \beta(1 - \delta))(1 - \beta) - \eta (\frac{1}{\beta} - v_{kk}) \frac{\bar{K}}{C}) v_{kk} + \eta (\frac{1}{\beta} - v_{kk}) \frac{\bar{K}}{C}$$

$$= v_{kk}^2 - \delta v_{kk} + \frac{1}{\beta}$$

$$\delta = (1 - \beta(1 - \delta))(1 - \beta) \frac{C}{\beta \bar{K}} + 1 + \frac{1}{\beta}$$

$$v_{kk} = \frac{\gamma}{2} - \sqrt{(\frac{\gamma}{2})^2 - \frac{1}{\beta}}$$

$$y_t = \alpha + \beta y_{t-1} + \varepsilon_t$$

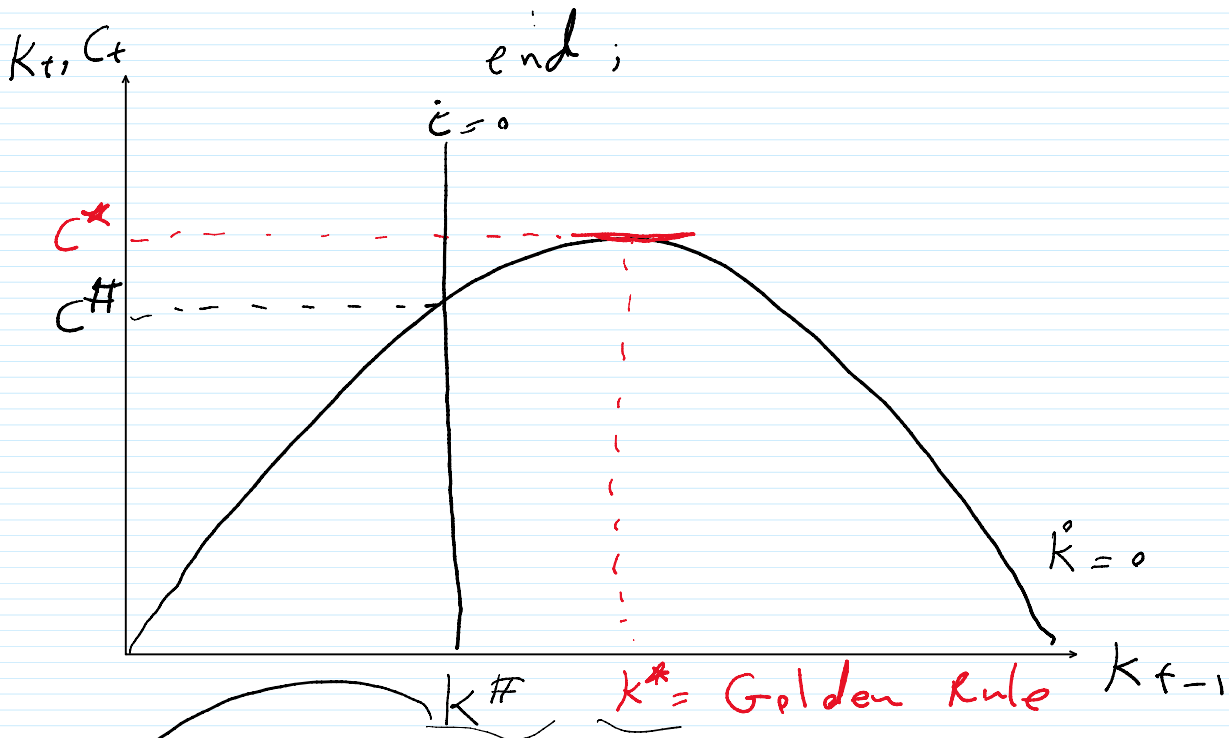
$$\hat{k}_t = v_{kk} \hat{k}_{t-1} + v_{kz} \frac{1}{z_t}$$

$$c_t = h c_{t-1} \quad \cdot \leq h < 1$$

Dynare:

بورد مقدمه

Var                     $\bar{c}$  مقمرون  
 Var exo                 $\bar{z}$  بوزن  
 Parameters            $\bar{h}$  بوزن  
 model (linear);



$$\frac{1}{1+\beta} = \beta = \frac{1}{R} = \frac{1}{1+\bar{r}}$$

$\bar{r} = \beta \rightarrow$  Deep Parameter

$$\beta > 0 \Rightarrow \bar{r} > 0$$



$$v = \sum_{t=0}^{\infty} \beta^t \left[ \frac{1}{1-\theta} + \frac{v(L_t)}{1-\chi} \right]$$

$$b_t + m_t = w_t L_t + (1+i_{t-1}) \frac{b_{t-1}}{1+\pi_t} + \frac{m_{t-1}}{1+\pi_t}, \quad w_t = \frac{W_t}{P_t}$$

$$\frac{B_t}{P_t}, \quad \frac{B_{t-1}}{P_t} = \underbrace{\left( \frac{B_{t-1}}{P_{t-1}} \right)}_{b_{t-1}} \frac{P_{t-1}}{P_t} = \frac{b_{t-1}}{P_t/P_{t-1}} = \frac{b_{t-1}}{1+\pi_t}$$

$$\frac{P_t - P_{t-1}}{P_{t-1}} = \frac{P_t}{P_{t-1}} - 1 \Rightarrow \frac{P_t}{P_{t-1}} = 1 + \pi_t$$

$$\sum_{t=0}^{\infty} \beta^t \left[ \frac{c_t^{1-\theta}}{1-\theta} + \frac{m_t^{1-\chi}}{1-\chi} - v(L_t) + \lambda_t \left( w_t L_t + \frac{m_{t-1}}{1+\pi_t} + (1+i_{t-1}) \frac{b_{t-1}}{1+\pi_t} - c_t - b_t - m_t \right) \right]$$

$$= c_t^{-\theta} - \lambda_t = 0$$

$$= m_t^{-\chi} - \lambda_t + \beta E_t \frac{\lambda_{t+1}}{1+\pi_{t+1}} = 0$$

$$= v'(L_t) - w_t \lambda_t = 0$$

$$= -\lambda_t + \beta E_t \frac{(1+i_t) \lambda_{t+1}}{1+\pi_{t+1}} = 0$$

max

s.t.

$$C_t + k$$

$$b_t =$$

$$m_t =$$

$$L = \frac{C_t}{r} + \frac{C_{t+1}}{r(1+r)}$$

$$\textcircled{1} \frac{\partial L}{\partial C_t}$$

$$\textcircled{2} \frac{\partial L}{\partial m_t}$$

$$\textcircled{3} \frac{\partial L}{\partial L_t}$$

$$\textcircled{4} \frac{\partial L}{\partial b_t}$$

$$\textcircled{5} -$$

$$1 + r_{t+1}$$

$$\frac{V'(L)}{C_t^{-\theta}} = w_t$$

فرض

$$\beta E_t \frac{\lambda_{t+1}}{1 + \pi_{t+1}} = \frac{\lambda_t}{1 + i_t}$$

$$m_t^{-\lambda} = \lambda_t - \frac{\lambda_t}{1 + i_t} = \frac{i_t}{1 + i_t} C_t^{-\theta}$$

$$\frac{m_t^{-\lambda}}{C_t^{-\theta}} = \frac{i_t}{1 + i_t} \Rightarrow m_t^{-\lambda} = \frac{i_t}{1 + i_t} C_t^{-\theta}$$

فرض

$$C_t^{-\theta} = \beta E_t \frac{(1 + i_t)}{1 + \pi_{t+1}} C_{t+1}^{-\theta} \Rightarrow$$

فرض

فرض

$$1 + r_{t+1} = E_t \frac{1 + i_t}{1 + \pi_{t+1}} \quad \text{Fisher Eq.}$$



$$E_t (r_{t+1}) (1 + E_t \pi_{t+1}) = 1 + i_t$$

$$E_t r_{t+1} + E_t \pi_{t+1} + E_t r_{t+1} E_t \pi_{t+1} = 1 + i_t$$

$$r_{t+1} = i_t - E_t \pi_{t+1} + E_t r_{t+1} E_t \pi_{t+1}$$



$$\begin{array}{r} - \quad a b_t \\ \textcircled{5} \quad \textcircled{1} \text{ } \underline{\textcircled{2}} \\ \quad \quad \quad \textcircled{3} \lambda_t \end{array}$$

①, ③

④

①, ②, ④

①, ④

(1 +

~~1 +~~

$E_t$

~~$$Y = C$$

$$Y = C + S$$

$$S = 0$$~~

$$Y_t = C_t$$

$$Y_t^{-\theta} = \beta \cdot E_t \left( \frac{(1+i_t)}{1+\pi_{t+1}} Y_{t+1}^{-\theta} \right)$$

New Keynesian IS

$$m_t^{-\alpha} = \frac{i_t}{1+i_t} Y_t^{-\theta}$$

$$M_t = \frac{M_t}{P_t} \rightarrow U_{r=0}$$

$$m_t^S = \frac{M_t^S}{P_t} \quad U_{r \neq 0}$$

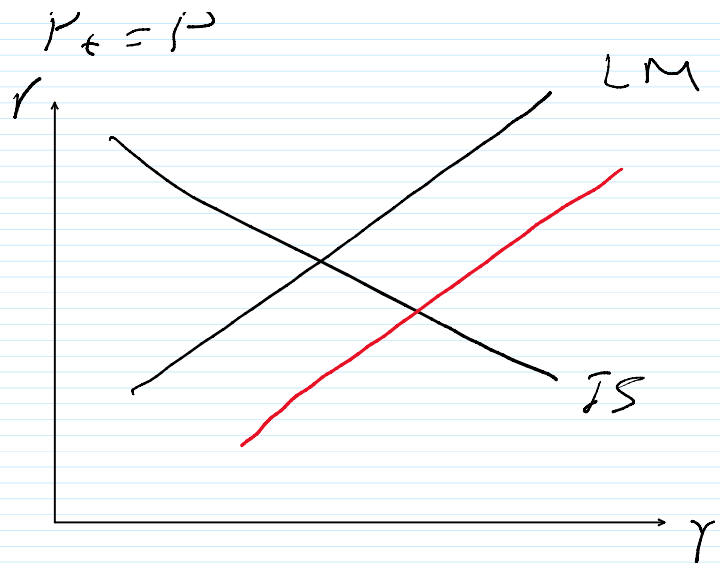
$$\bar{m}_t^S = m_t^d = \bar{m}_t$$

$$\bar{m}_t^{-\alpha} = \left( \frac{i_t}{1+i_t} \right) Y_t^{-\theta} \quad LM$$

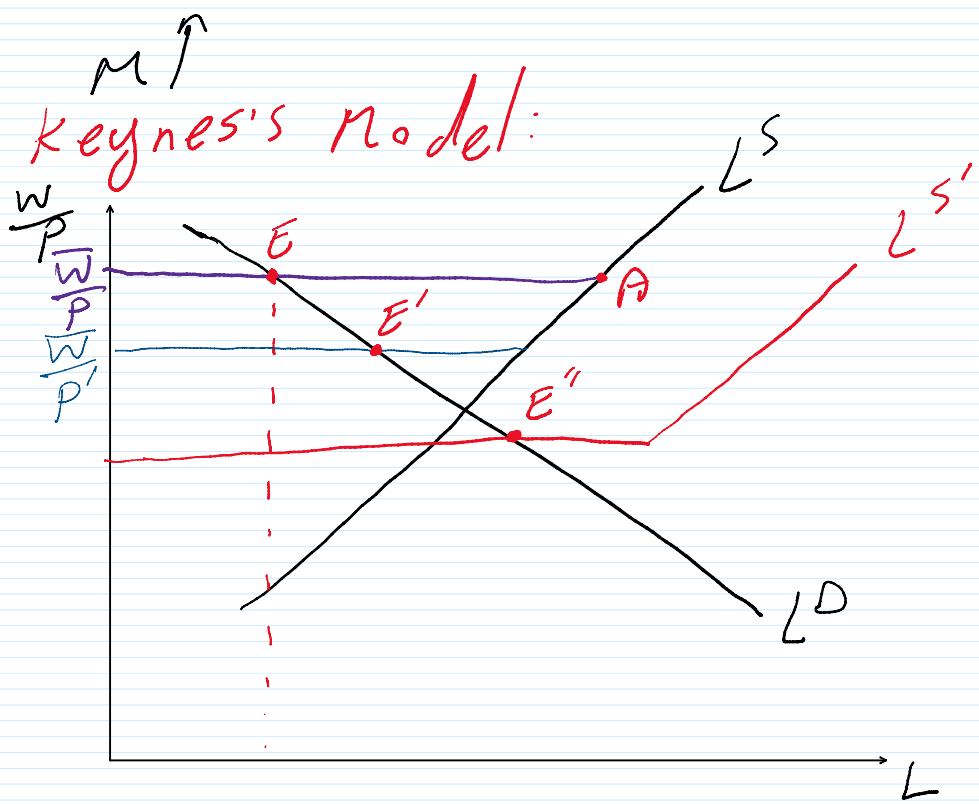
$$\Rightarrow \ln Y_t = a + \ln E_t Y_{t+1} - \frac{1}{\theta} (r) \quad IS$$

$$a \equiv - \left( \frac{1}{\theta} \right) \ln \beta$$

$$P_t = \bar{P} \quad , \quad LM$$



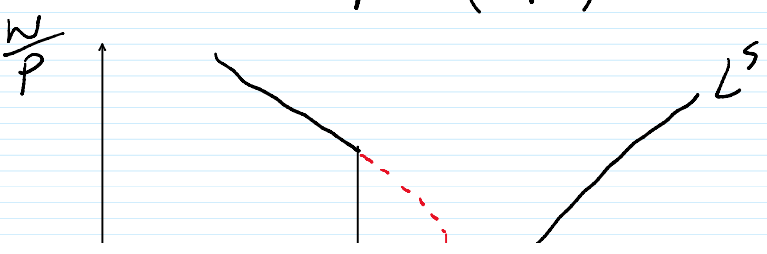
2: Keynes's Model:



$$L = L^S\left(\frac{w}{p}\right) \quad L^{S'}(\cdot) > \cdot$$

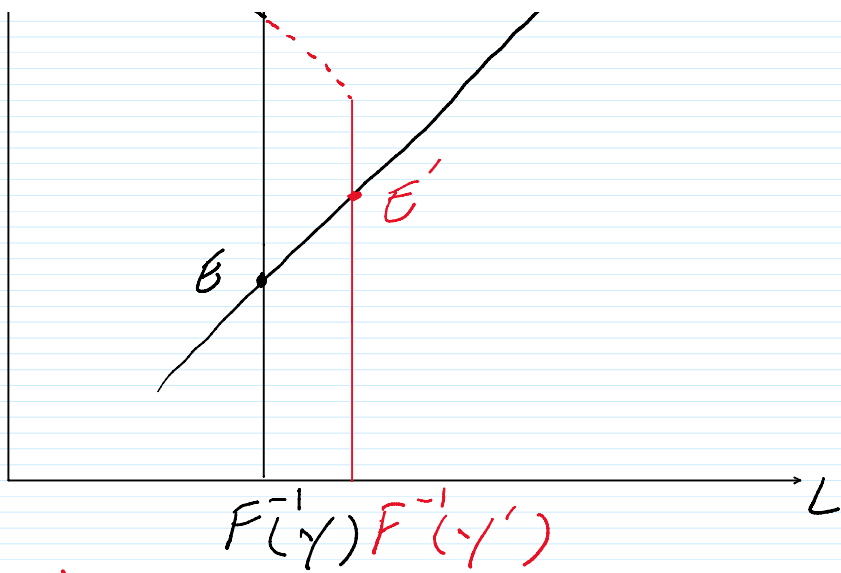
$$Y = F(L)$$

$$L = F^{-1}(Y)$$



Case 2

$P' > P$



sticky prices, flexible wages and Real  
Market imperfections:

$$\underbrace{\pi_t - E_t \pi_{t+1}}_{\text{sub } \pi_t} = f(u_t - \bar{u})$$

NAIRU

Non-Accelerating Inflation Rate of Unemployment

$$\pi_t - E_t \pi_{t+1} = g(\underbrace{Y_t - Y^P}_{\text{sub } Y_t})$$

cy wage  
ge Function

Case 3:

Lab 0

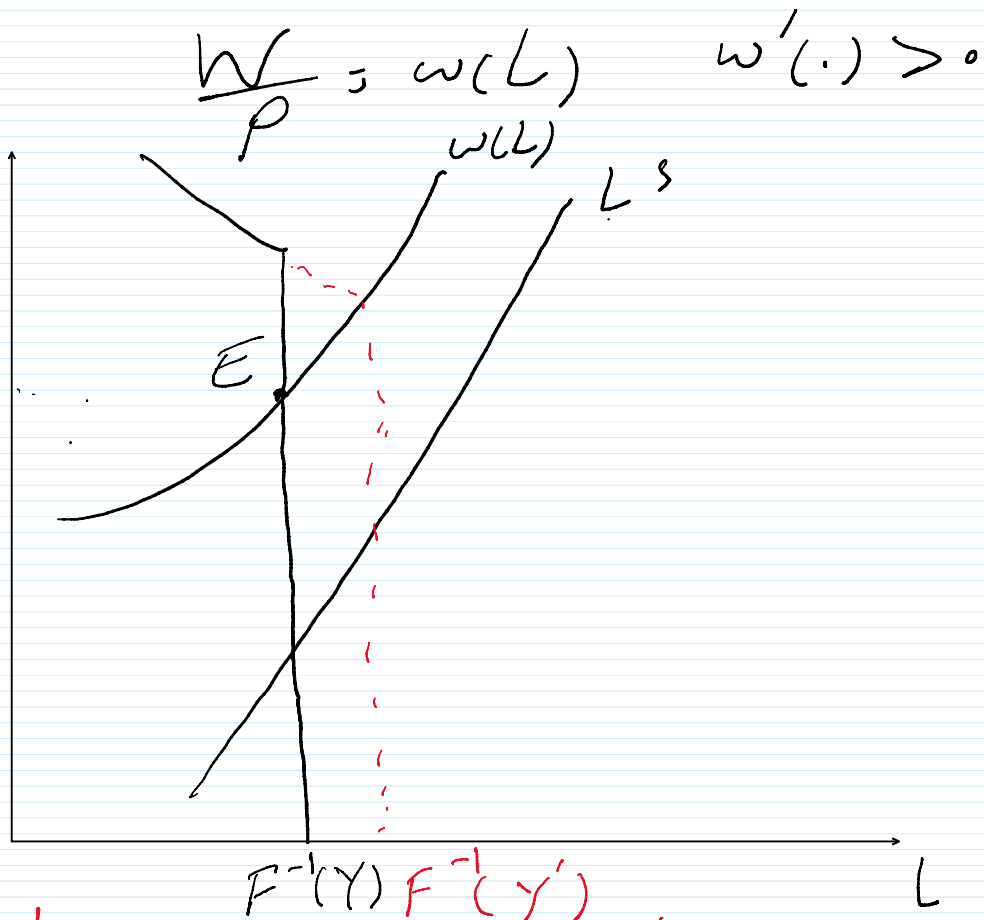
1

N

Efficient

real-way

age 1 - ...



Sticky Wage, Flexible Prices, and Competition:

$$P = MC$$

$$R = P(1 + \eta)$$

$$= \frac{1}{1 + \eta} MC$$

$$\frac{1}{1 + \eta} > 1 \quad \text{Markup}$$

real-way

$$\frac{w}{P}$$

Case 4: St.

Imperfect

$$MR =$$

$$MC = M$$

$$P =$$

$$\eta < 0$$



$$= \frac{1}{1 + \eta} > 1 \quad \text{Markup}$$

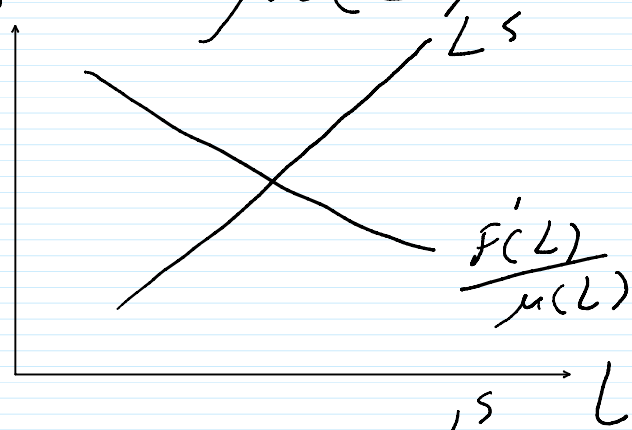
$$\frac{Y}{L} = w$$

$$MP_L = (w)$$

$$= \frac{w}{\frac{\partial Y}{\partial L}} = MC = \frac{w}{MP_L} = \frac{w}{F'(L)}$$

$$p = \mu(L) \frac{w}{F'(L)}$$

$$\frac{w}{p} = \frac{F'(L)}{\mu(L)}$$



h


$$P \frac{\partial}{\partial}$$

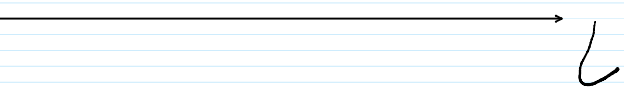
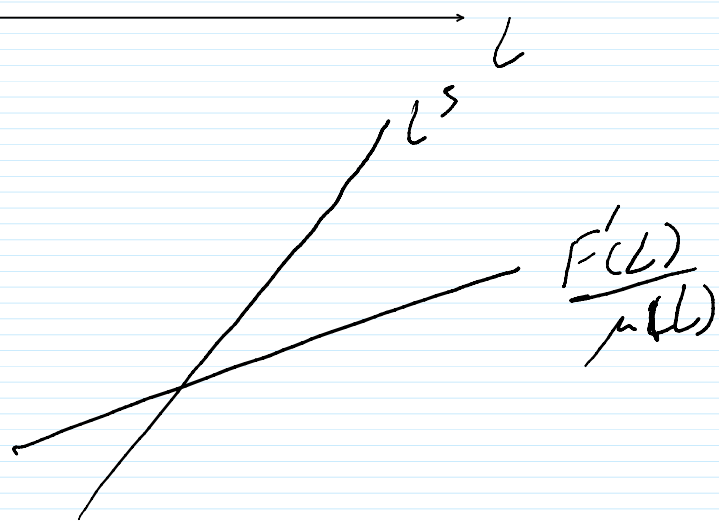
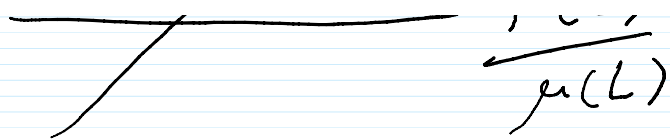
$$P \frac{\partial}{\partial}$$

$$P$$

f

$$\frac{w}{p}$$

$$\frac{w}{p}$$




$$E_t \pi_{t+1} = f(y_t - \bar{y})$$

$$\pi_t - \pi_{t-1} = f(\underbrace{y_t - \bar{y}}_{\tilde{y}_t}) = \lambda \tilde{y}_t \quad \lambda > 0 \text{ NKPC}$$

$$E_t \pi_{t+1} + \frac{1}{1+\phi} \pi_{t-1} + \lambda \tilde{y}_t$$

$$r_t = b \tilde{y}_t \quad b > 0 \quad \text{Taylor Rule}$$

1, ., F^S, a, .

$\frac{w}{p}$  $\pi_t -$  $\pi_t -$  $\pi$ 

$$\pi_t = \frac{\phi}{1 + \phi}$$

 $\}$

$$r_t = E_t y_{t+1} - \frac{1}{\theta} r_t + u_t^{IS} \quad \theta > 0$$

$$u_t^{IS} = \rho_{IS} u_{t-1}^{IS} + e_t^{IS} \quad -1 < \rho_{IS} < 1$$

$$\pi_t = \pi_{t-1} + \lambda y_t$$

$$-\frac{1}{\theta} b y_t + u_t^{IS}$$

$$E_t y_{t+1} + u_t^{IS}$$

$$\underbrace{\frac{\theta}{\theta+b}}_{\phi} E_t y_{t+1} + \underbrace{\frac{\theta}{\theta+b}}_{\phi} u_t^{IS}$$

$$E_t y_{t+1} + \phi u_t^{IS}$$

$$\frac{1}{\phi \rho_{IS}^s} u_t^{IS} + \lim_{s \rightarrow \infty} \phi^s E_t y_{t+s}$$

$$\left\{ \begin{array}{l} y \\ \vdots \\ \vdots \end{array} \right.$$

$$y_t = E_t y_{t+1}$$

$$\left( \frac{\theta + b}{\theta} \right) y_t =$$

$$y_t = \frac{c}{\theta}$$

$$y_t = \phi$$

$$y_t = \frac{\phi}{1}$$

$$\frac{b - \theta \beta \bar{r}}{\theta + b - \theta \beta \bar{r}} u_t^{\bar{r}}$$

$$\frac{-1 + \lambda \theta}{\theta + b - \theta \beta \bar{r}} u_t^{\bar{r}}$$



$$= E_t y_{t+1} - \frac{1}{\theta} (i_t - E_t \pi_{t+1}) \cdot u_t^{\bar{r}}$$
$$= b_y y_t + b_\pi \pi_t + u_t^i$$

$$y_t = \frac{\theta}{\theta + 1}$$

$$\pi_t = \pi_t$$



$$y_t =$$

$$z_t =$$