

# "Open Source Macroeconomics Laboratory Boot Camp Perturbation Methods"

Kerk L. Phillips

July 19, 2019

# Outline

- 1 Solution with "Jump" Variables ( $Y_t$ )
- 2 Introduction and Motivation
- 3 Perturbation Methods in General
- 4 Brock and Mirman Model
- 5 Perturbation in DSGE Models

# Types of Variables

- $Z_t$  is a vector of  $n_Z$  exogenous state variables.
- $X_{t-1}$  is a vector of  $n_X$  endogenous state variables.
- $Y_t$  is a vector of  $n_Y$  implicitly-defined non-state or "jump" variables.
- $D_t$  is a vector of  $n_D$  explicitly-defined non-state or "jump" variables.

Note we can lump  $Y_t$  and  $D_t$  into  $X_t$  if we like. This may increase computational cost, but is otherwise sound logically. We are searching for a policy function  $X_t = \Phi(X_{t-1}, Z_t)$ , and perhaps a jump function  $Y_t = \Psi(X_{t-1}, Z_t)$ .

# Dynamic Behavior

We will take the characterizing equations for the model and write them as a vector of two sets of functions stacked in the following form:

$$\Gamma_Y(X_t, X_{t-1}, Y_t, Z_{t+1}, Z_t) = 0 \quad (1)$$

$$E_t\{\Gamma_X(X_{t+1}, X_t, X_{t-1}, Y_{t+1}, Y_t, Z_{t+1}, Z_t)\} = 0 \quad (2)$$

$X_{t+1}$ ,  $X_t$  and  $X_{t-1}$  are  $n_X \times 1$  vectors.  $Y_{t+1}$  and  $Y_t$  are  $n_Y \times 1$  vectors.  $Z_{t+1}$  and  $Z_t$  are  $n_Z \times 1$  vectors and  $\Gamma$  outputs a  $n_X \times 1$  vector.

# Dynamic Behavior

We can use a first-order Taylor-series approximation of these equations to get a linear approximation of the characterizing equations.

$$A\tilde{X}_t + B\tilde{X}_{t-1} + C\tilde{Y}_t + D\tilde{Z}_t = 0 \quad (3)$$

$$E_t \left\{ F\tilde{X}_{t+1} + G\tilde{X}_t + H\tilde{X}_{t-1} + J\tilde{Y}_{t+1} + K\tilde{Y}_t + L\tilde{Z}_{t+1} + M\tilde{Z}_t \right\} = 0 \quad (4)$$

where  $\tilde{X}_t$  denotes  $X_t - \bar{X}$

Linear approximations of policy and jump functions are:

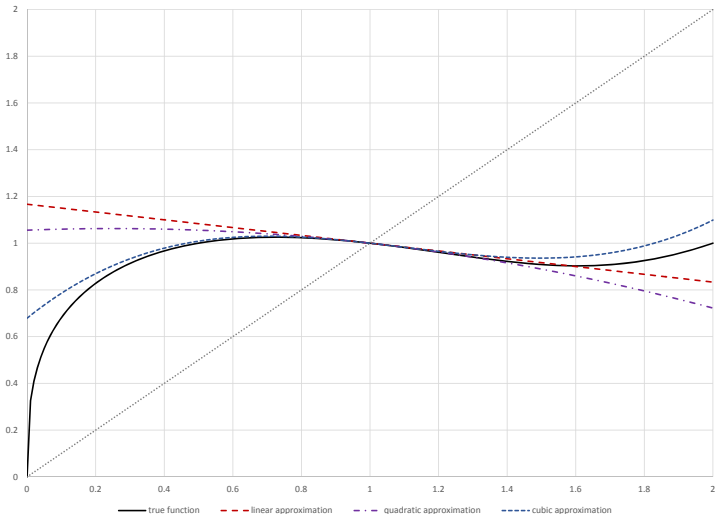
$$\tilde{X}_t = U + P\tilde{X}_{t-1} + Q\tilde{Z}_t \quad (5)$$

$$\tilde{Y}_t = V + R\tilde{X}_{t-1} + S\tilde{Z}_t \quad (6)$$

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# Illustration of Polynomial Approximations



Linear approximation is:

$$\tilde{X}_t = P\tilde{X}_{t-1} + Q\tilde{Z}_t$$

Quadratic approximation is:

$$\tilde{X}_t = H_X\tilde{X}_{t-1} + H_Z\tilde{Z}_t + \frac{1}{2} \left[ H_{XX}\tilde{X}_{t-1}^2 + H_{ZZ}\tilde{Z}_t^2 + 2H_{XZ}\tilde{X}_{t-1}\tilde{Z}_t \right]$$



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# First-Order Peturbations

Suppose we have a condition on a potentially nonlinear bivariate function:

$$F(x, u) = 0 \quad (7)$$

Assume  $u$  is an exogenously given variable, and  $x$  will be chosen to satisfy (7). Denote the solution to this condition as  $x(u)$  and assume that the value of  $x(u_0)$  is known.

# First-Order Peturbations

Taking the derivative of (7) with respect to  $u$  gives:

$$F_x\{x(u), u\}x_u(u) + F_u\{x(u), u\} = 0 \quad (8)$$

If we evaluate this at  $u = u_0$  and solve for the first derivative of  $x(u)$ , we have:

$$x_u(u_0) = -\frac{F_u\{x(u_0), u_0\}}{F_x\{x(u_0), u_0\}}$$

# First-Order Perturbations

Since  $x(u_0)$  is known, as long as  $F_x\{x(u_0), u_0\} \neq 0$  we can find the value for the first derivative. The first-order (linear) Taylor-series approximation of  $x(u)$  will be:

$$x(u) = x(u_0) + x_u(u_0)(u - u_0)$$

## Second-Order Perturbations

To find the second-order terms we differentiate (8) again with respect to  $u$ .

$$\begin{aligned} & F_{xx}\{x(u), u\}x_u(u)x_u(u) + F_{xu}\{x(u), u\}x_u(u) \\ & + F_x\{x(u), u\}x_{uu}(u) + F_{xu}\{x(u), u\}x_u(u) \\ & + F_{uu}\{x(u), u\} = 0 \end{aligned}$$

## Second-Order Perturbations

Again evaluating at  $u = u_0$  and solving this time for the second derivative of  $x(u)$ , we have:

$$x_{uu}(u_0) = -\frac{F_{xx}\{x(u_0), u_0\}[x_u(u_0)]^2 + 2F_{xu}\{x(u_0), u_0\}x_u(u_0) + F_{uu}}{F_x\{x(u_0), u_0\}}$$

Hence, the second-order (quadratic) Taylor-series approximation of  $x(u)$  will be:

$$x(u) = x(u_0) + x_u(u_0)(u - u_0) + \frac{1}{2}x_{uu}(u_0)(u - u_0)^2$$

# High-Order Perturbations

Higher order terms can be obtained by successive differentiation, setting  $u = u_0$  and solving for the appropriate derivative.

Each will be a function of the various derivatives of  $F(x, u)$  and the lower-order derivatives of  $x(u)$  obtained from previous iterations.

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# Brock and Mirman

Recall the Euler equation for the non-stochastic version of the model is:

$$\frac{1}{K_t^\alpha - K_{t+1}} - \beta \frac{\alpha K_{t+1}^{\alpha-1}}{K_{t+1}^\alpha - K_{t+2}} = 0$$

In terms of our notation from the previous section we have:

$$u = K_t$$

$$x = x(u) = K_{t+1}$$

$$y = x(x) = K_{t+2}$$

$$F(y, x, u) = F(y(x(u)), x(u), u)$$

$$= \frac{1}{K_t^\alpha - K_{t+1}} - \beta \frac{\alpha K_{t+1}^{\alpha-1}}{K_{t+1}^\alpha - K_{t+2}} = 0 \quad (9)$$

# Differentiate

Take the derivative of (9) with respect to  $u = K_t$ :

$$F_y(y(x(u)), x(u), \bar{u})x_u(x(u))x_u(u) + F_x(y(x(u)), x(u), u)x_u(u) + F_u(y(x(u)), x(u), u) = 0 \quad (10)$$

# Differentiate

Evaluating (10) at  $u = \bar{u} = \bar{K}$  and noting that  $x(\bar{u}) = \bar{u}$ :

$$\begin{aligned}
 &F_y(y(x(\bar{u})), x(\bar{u}), \bar{u})x_u(x(\bar{u}))x_u(\bar{u}) \\
 &+ F_x(y(x(\bar{u})), x(\bar{u}), \bar{u})x_u(\bar{u}) + F_u(y(x(\bar{u})), x(\bar{u}), \bar{u}) = 0 \\
 &F_y(\bar{u}, \bar{u}, \bar{u})x_u(\bar{u})^2 + F_x(\bar{u}, \bar{u}, \bar{u})x_u(\bar{u}) + F_u(\bar{u}, \bar{u}, \bar{u}) = 0
 \end{aligned}$$

Note that  $F_y(\bar{u}, \bar{u}, \bar{u})$  is the same as  $F$  from the linearization notes. Similarly,  $F_x(\bar{u}, \bar{u}, \bar{u})$  is  $G$ , and  $F_u(\bar{u}, \bar{u}, \bar{u})$  is  $H$ . Also note that  $x_u(\bar{u})$  is  $P$ . As in those notes the value of  $x_u(\bar{u})$  comes from solving a quadratic.

# Differentiate Again

$$\begin{aligned}
 & F_{yy}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^4 + F_{yx}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^3 \\
 & + F_{yu}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^2 + F_y(\bar{u}, \bar{u}, \bar{u}) x_{uu}(\bar{u}) x_u(\bar{u})^2 \\
 & + F_y(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u}) x_{uu}(\bar{u}) + F_{yx}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^3 \\
 & + F_{xx}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^2 + F_{xu}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u}) \\
 & + F_x(\bar{u}, \bar{u}, \bar{u}) x_{uu}(\bar{u}) + F_{yu}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u})^2 \\
 & + F_{xu}(\bar{u}, \bar{u}, \bar{u}) x_u(\bar{u}) + F_{uu}(\bar{u}, \bar{u}, \bar{u}) = 0
 \end{aligned}$$

# Differentiate Again

Supressing the function arguments for the sake of clarity we can rewrite (??) as below.

$$(F_{yy} x_u^4 + 2F_{yx} x_u^3 + 2F_{yu} x_u^2 + F_{xx} x_u^2 + 2F_{xu} x_u + F_{uu}) + (F_y x_u^2 + F_y x_u + F_x)x_{uu} = 0$$

Note the  $F_{ij}$  are all second-derivatives evaluated at the steady state. Since  $x_u$  has already been solved we can solve this for  $x_{uu}$ .

# Differentiate Again

$$x_{uu} = - \frac{F_{yy} x_u^4 + 2F_{yx} x_u^3 + 2F_{yu} x_u^2 + F_{xx} x_u^2 + 2F_{xu} x_u + F_{uu}}{(F_y x_u^2 + F_y x_u + F_x)}$$

The quadratic approximation to the policy function is given by:

$$\tilde{K}_{t+1} = x_u \tilde{K}_t + \frac{1}{2} x_{uu} \tilde{K}_t^2 \quad (11)$$

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# DSGE Perturbation

Write our stacked dynamic equations as:

$$E_t\{\Gamma(X_{t+1}, X_t, X_{t-1}, Y_{t+1}, Y_t, Z_{t+1}, Z_t)\} = 0 \quad (12)$$

Recall the exogenous law of motion:

$$Z_t = NZ_{t-1} + v\Omega\varepsilon_t; \varepsilon_t \sim (0, I_{n_Z}) \quad (13)$$

where  $v$  is a scalar, and  $\Omega$  is a matrix that determines correlations of the elements in  $\varepsilon_t$ .

The policy function and jump functions are:

$$X_t = H(X_{t-1}, Z_t, v) \quad (14)$$

$$Y_t = G(X_{t-1}, Z_t, v) \quad (15)$$



# DSGE Perturbation

For notational ease define the following.

$$A_t \equiv [X_{t+1} \quad X_t \quad X_{t-1} \quad Y_{t+1} \quad Y_t \quad Z_{t+1} \quad Z_t]^T$$

$$S_t \equiv [X_{t-1} \quad Z_t \quad v]$$

$$n_A \equiv 3n_X + 2n_Y + 2n_Z$$

$$n_S \equiv n_X + n_Z + 1$$

# DSGE Perturbation

The Taylor-series approximation of  $\Gamma$  with second-order terms for the variance is:

$$\Gamma(A_t) \doteq \Gamma(\bar{X}, \dots, \bar{Z}) + [\Gamma_1 \quad \dots \quad \Gamma_7] \begin{bmatrix} \tilde{X}_{t+1} \\ \vdots \\ \tilde{Z}_t \end{bmatrix} + \frac{1}{2} \left( I_{n_A} \otimes \begin{bmatrix} \tilde{X}_{t+1} & \vdots & \tilde{Z}_t \end{bmatrix} \right) \begin{bmatrix} \Gamma_{11} & \dots & \Gamma_{17} \\ \vdots & \ddots & \vdots \\ \Gamma_{71} & \dots & \Gamma_{77} \end{bmatrix} \begin{bmatrix} \tilde{X}_{t+1} \\ \vdots \\ \tilde{Z}_t \end{bmatrix} \quad (16)$$

$\Gamma_1$  through  $\Gamma_7$  are combinations of the  $A$  through  $M$  matrices in Uhlig's notation.  $\Gamma_{11}$  through  $\Gamma_{77}$  are all Magnus and Neudecker matrices of second-order coefficients.

# Using 3-Dimensional Tensors

We need to get a matrices of first and second derivatives for the functions  $\Gamma$ ,  $H$ , and  $G$ . All of these are vector-valued functions of vectors.

- The outputs are 1-dimensional
- The Jacobians are 2-dimensional
- The Hessians are 3-dimensional

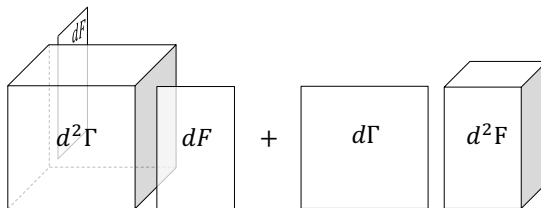
We can either work with matrix algebra extended beyond two dimensions - tensors. Or we can restack 3-dimensional matrices into two dimensions. The latter is what Magnus and Neudecker (1999) discuss.

# Using Tensors

$$\Gamma(A) = 0; \quad A = F(S)$$

$$\Gamma_F(F(S))F_S(S) = 0$$

$$F_S(S)^T \Gamma_{FF} F_S(S) + \Gamma_F(F(S)) F_{SS}(S)$$



Let's NOT do this.

# Magnus and Neudecker Matrices

If  $Y = F(X)$  is a vector-valued function of a vector input.  
Then the Magnus and Neudecker Jacobian is:

$$\begin{bmatrix} \frac{\partial Y_1}{\partial X_1} & \cdots & \frac{\partial Y_1}{\partial X_{n_X}} \\ \vdots & \ddots & \vdots \\ \frac{\partial Y_{n_Y}}{\partial X_1} & \cdots & \frac{\partial Y_{n_Y}}{\partial X_{n_X}} \end{bmatrix}$$

The Hessian is...

# Magnus and Neudecker Matrices

$$\begin{bmatrix} \frac{\partial^2 Y_1}{\partial X_1 \partial X_1} & \cdots & \frac{\partial^2 Y_1}{\partial X_{n_X} \partial X_1} \\ \vdots & \ddots & \vdots \\ \frac{\partial^2 Y_{n_Y}}{\partial X_1 \partial X_1} & \cdots & \frac{\partial^2 Y_{n_Y}}{\partial X_{n_X} \partial X_1} \\ \frac{\partial^2 Y_1}{\partial X_1 \partial X_2} & \cdots & \frac{\partial^2 Y_1}{\partial X_{n_X} \partial X_2} \\ \vdots & \ddots & \vdots \\ \frac{\partial^2 Y_{n_Y}}{\partial X_1 \partial X_2} & \cdots & \frac{\partial^2 Y_{n_Y}}{\partial X_{n_X} \partial X_2} \\ \vdots & & \vdots \\ \frac{\partial^2 Y_1}{\partial X_1 \partial X_{n_X}} & \cdots & \frac{\partial^2 Y_1}{\partial X_{n_X} \partial X_{n_X}} \\ \vdots & \ddots & \vdots \\ \frac{\partial^2 Y_{n_Y}}{\partial X_1 \partial X_{n_X}} & \cdots & \frac{\partial^2 Y_{n_Y}}{\partial X_{n_X} \partial X_{n_X}} \end{bmatrix}$$

# DSGE Perturbation

The Taylor-series approximation of  $H$  with second-order terms for the variance is:

$$\begin{aligned}
 H(X_{t-1}, Z_t, v) \doteq H(\bar{X}, \bar{Z}, \bar{v}) + [H_X \quad H_Z \quad H_v] \begin{bmatrix} \tilde{X}_{t-1} \\ \tilde{Z}_t \\ \tilde{v} \end{bmatrix} \\
 + \frac{1}{2} \left( I_{n_Y+n_X} \otimes \begin{bmatrix} \tilde{X}_{t-1}^T & \tilde{Z}_t^T & \tilde{v} \end{bmatrix} \right) \begin{bmatrix} H_{XX} & H_{XZ} & 0 \\ H_{ZX} & H_{ZZ} & 0 \\ 0 & 0 & H_{vv} \end{bmatrix} \begin{bmatrix} \tilde{X}_{t-1} \\ \tilde{Z}_t \\ \tilde{v} \end{bmatrix}
 \end{aligned}
 \tag{17}$$

$H_X$  and  $H_Z$  terms are the  $P$  and  $Q$  matrices in Uhlig's notation.  $H_{XX}$ ,  $H_{ZZ}$ ,  $H_{ZX}$ ,  $H_{XZ}^T$  and  $H_{vv}$  are all Magnus and Neudecker matrices of second-order coefficients.

# DSGE Perturbation

A similar setup is used for the approximation of the  $G$  function.

$$\begin{aligned}
 G^k(X_{t-1}, Z_t, v) \doteq G(\bar{X}, \bar{Z}, \bar{v}) &+ [G_X \quad G_Z \quad G_v] \begin{bmatrix} \tilde{X}_{t-1} \\ \tilde{Z}_t \\ \tilde{v} \end{bmatrix} \\
 &+ \frac{1}{2} \left( I_{n_Y+n_X} \otimes \begin{bmatrix} \tilde{X}_{t-1}^T & \tilde{Z}_t^T & \tilde{v} \end{bmatrix} \right) \begin{bmatrix} G_{XX} & G_{XZ} & 0 \\ G_{ZX} & G_{ZZ} & 0 \\ 0 & 0 & G_{vv} \end{bmatrix} \begin{bmatrix} \tilde{X}_{t-1} \\ \tilde{Z}_t \\ \tilde{v} \end{bmatrix}
 \end{aligned}
 \tag{18}$$

$G_X$  and  $G_Z$  terms are the  $R$  and  $S$  matrices in Uhlig's notation.



# DSGE Perturbation

We can substitute (14), (15) and (13) into our definition of  $A_t$  to get the following function:

$$A_t = F(S_t) = \begin{bmatrix} H(H(X_{t-1}, Z_t, v), NZ_t + v\Omega\varepsilon_{t+1}, v) \\ H(X_{t-1}, Z_t, v) \\ X_{t-1} \\ G(H(X_{t-1}, Z_t, v), NZ_t + v\Omega\varepsilon_{t+1}, v) \\ G(X_{t-1}, Z_t, v) \\ NZ_{t-1} + v\Omega\varepsilon_t \\ Z_t \end{bmatrix} \quad (19)$$

See the chapter handout for the Jacobian and Hessian matrices,  $F_S(S_t)$  and  $F_{SS}(S_t)$ .

# DSGE Perturbation

Using (19) in (12) we get  $\Delta(S_t) \equiv \Gamma(F(S_t)) = 0$ . Magnus and Neudecker (1999) show that the chain-rule for this function with our setup for the organization of the Jacobian and Hessian matrices is as follows.

$$\Delta_{SS} = (F_S \otimes I_{n_X+n_Y})^T \Gamma_{AA} F_S + (I_{n_S} \otimes \Gamma_A) F_{SS} \quad (20)$$

# Solving for Linear Terms

We can solve for the linear terms as we did in the linearization chapter. This will generate the coefficient matrices  $H_X$ ,  $H_Z$ ,  $G_X$  and  $G_Z$ . (Uhlig's  $P$ ,  $Q$ ,  $R$  and  $S$ .) Discussion in the chapter shows that  $H_V$  and  $G_V$  are zero.

# Solving for Quadratic Terms

With the first-order coefficients for the  $H$  and  $G$  functions known, we can use the expectation of (20) to solve for the second-order coefficients. We note that  $F_S$  is a function of the first-order coefficients as shown in the chapter handout. Similarly, we know that  $F_{SS}$  a function of both the first and second-order coefficients.

# Solving for Quadratic Terms

Before taking expectations, we need to multiply out the term  $\Lambda \equiv (F_S \otimes I_{n_X+n_Y})^T \Gamma_{AA} F_S$ . Examine the  $F_S$  matrix and note that terms with  $\varepsilon_{t+1}$  appear only in the third column.

$$F_S = \begin{bmatrix} H_X H_X & H_X H_Z + H_Z N & H_X H_V + H_Z \Omega \varepsilon_{t+1} + H_V \\ H_X & H_Z & H_V \\ 1 & 0 & 0 \\ G_X H_X & G_X H_Z + G_Z N & G_X H_V + G_Z \Omega \varepsilon_{t+1} + G_V \\ G_X & G_Z & G_V \\ 0 & N & \Omega \varepsilon_{t+1} \\ 0 & 1 & 0 \end{bmatrix}$$

# Solving for Quadratic Terms

If we take the expectation of  $F_S$  the  $\varepsilon_{t+1}$  terms disappear.

$$E\{F_S\} = \begin{bmatrix} H_X H_X & H_X H_Z + H_Z N & H_X H_V + H_V \\ H_X & H_Z & H_V \\ 1 & 0 & 0 \\ G_X H_X & G_X H_Z + G_Z N & G_X H_V + G_V \\ G_X & G_Z & G_V \\ 0 & N & 0 \\ 0 & 1 & 0 \end{bmatrix}$$

# Solving for Quadratic Terms

Let's look at the  $(3, 3)$  block in  $\Lambda$ . Recall that  $H_v$  and  $G_v$  are zeros.

$$\Lambda(3, 3) = \varepsilon_{t+1}^T (\Omega H_Z^T \Gamma_{11} H_Z \Omega + \Omega G_Z^T \Gamma_{44} G_Z \Omega) \varepsilon_{t+1}$$

This is the only term where the quadratic form of  $\varepsilon_{t+1}$  appears. In every other term it is either absent or appears as a linear term. Hence when expectations are taken the terms with  $\varepsilon_{t+1}$  disappear. This means we can use

$E\{\Lambda\} = (E\{F_S\} \otimes I_{n_X+n_Y})^T \Gamma_{AA} E\{F_S\}$  and then replace the  $(3, 3)$  term.

# Solving for Quadratic Terms

To take expectations of  $\Lambda(3, 3)$  it is useful to know that if the elements of a column vector of random variables  $\varepsilon \sim iid(0, I)$ , then  $E\{\varepsilon^T A \varepsilon\} = \text{tr}(A)$ .

So we replace the zero in the  $(3, 3)$  block with  $\text{tr}(\Omega[H_Z^T \Gamma_{11} H_Z] + [G_Z^T \Gamma_{44} G_Z] \Omega)$ .



# Solving for Quadratic Terms

Recall equation (20):

$$\Delta_{SS} = (F_S \otimes I_{n_X+n_Y})^T \Gamma_{AA} F_S + (I_{n_S} \otimes \Gamma_A) F_{SS}$$

Unfortunately,  $I_{n_A} \otimes \Gamma_A$  is not a square matrix and therefore not invertable. However, we can solve for the second-order coefficients numerically.

# Solving for Quadratic Terms

The coefficients we need to find are

$\Theta = \{H_{XX}, H_{XZ}, H_{ZZ}, H_{VV}, G_{XX}, G_{XZ}, G_{ZZ}, G_{VV}\}$ .  $E\{F_S\}$ ,  $\Gamma_A$  and  $\Gamma_{AA}$  are known. We can therefore write a  $\Delta_{SS}$  function as shown below and numerically solve for the values of  $\Theta$  that set it equal to zero. We note that  $\Delta_{SS}$  will return a matrix of size  $n_S(n_X + n_Y) \times n_S$ . This will be  $n_X + n_Y$  blocks of symmetric  $n_S \times n_S$  matrices.

$$\Delta_{SS}(\Theta) = (E\{\Lambda\} + (I_{n_S} \otimes \Gamma_A)E\{F_{SS}(\Theta)\}) = 0$$

$$\Lambda = (F_S \otimes I_{n_X+n_Y})^T \Gamma_{AA} F_S$$

## Solving for Quadratic Terms

The symmetric blocks in the  $\Delta_{SS}$  matrix will be denoted  $\Delta_{SS}^i$  for  $i \in \{1, 2, \dots, n_X + n_Y\}$  and can be decomposed into nine parts.

$$\Delta_{SS}^i = \begin{bmatrix} \Delta_{XX}^i & \Delta_{XZ}^i & 0 \\ (\Delta_{XZ}^i)^T & \Delta_{ZZ}^i & 0 \\ 0 & 0 & \Delta_{VV}^i \end{bmatrix} \quad (21)$$

Hence we have  $n_X^2 + n_Z^2 + n_X n_Z + 1$  unique values for each  $i$ , for a total of  $(n_X^2 + n_Z^2 + n_X n_Z + 1)(n_X + n_Y)$ . We have  $(n_X^2 + n_X n_Z + n_Z + 1)n_X$  terms in the  $H_{SS}$  coefficients and  $(n_X^2 + n_X n_Z + n_Z + 1)n_Y$  terms in the  $G_{SS}$  coefficients. Hence the  $\Delta_{SS} = 0$  condition will exactly identify  $\Theta$ .

To summarize. We get the quadratic terms by:

- Taking first and second derivatives of the  $\Gamma$  function at the steady state:  $\Gamma_A$  and  $\Gamma_{AA}$ .
- Finding the first order terms:  $H_X$  and  $H_Z$ .
- These allow us to get  $E\{F_S\}$ .
- We then use a numerical equation solver to solve for  $\Theta = \{H_{XX}, H_{XZ}, H_{ZZ}, H_{ww}, G_{XX}, G_{XZ}, G_{ZZ}, G_{ww}\}$ , which are inputs into the  $F_{SS}$  function in the equation below.
- The (3.3) element of  $\Lambda$  is assigned as discussed.

$$\Delta_{SS}(\Theta) = 0$$

$$E\{\Lambda\} + (I_{n_S} \otimes \Gamma_A)E\{F_{SS}(\Theta)\} = 0$$

$$E\{(F_S \otimes I_{n_X+n_Y})^T \Gamma_{AA} F_S\} + (I_{n_S} \otimes \Gamma_A)E\{F_{SS}(\Theta)\} = 0$$