$$\frac{1}{\sqrt{\left(\frac{y_{\tau}}{y_{\tau}}\right)^{2}}} \frac{1}{\sqrt{\left(\frac{x_{\tau}}{x_{\tau}}\right)^{2}}} \frac{1}{\sqrt{\left(\frac{x_{\tau}}{x_{\tau}}\right)^{2}}}} \frac{1}{\sqrt{\left(\frac{x_{\tau}}{x_{\tau}}\right)^{2}}} \frac{1}{\sqrt{\left(\frac{x_{\tau}}{x_{\tau}}\right)^{2}$$

$$\frac{1}{4} = \frac{1}{2} \ln \left( \frac{y_{1}y_{1}}{y_{1}} \right) = \frac{1}{2} \ln y_{1} - \frac{y_{1}}{y_{1}} + \ln d_{1} - \frac{y_{1}}{y_{1}} \left( \alpha_{1} \right) - \ln d_{1} + \frac{1}{2}$$

$$= \ln y_{1} - \frac{y_{1}}{y_{1}} + \ln d_{1} - \frac{y_{1}}{y_{1}} \left( \alpha_{1} \right) - \ln d_{1} + \frac{1}{2}$$

$$\frac{1}{2} \nabla^{\lambda} = \frac{\partial \ln f(y_t / y_{t-1})}{\partial f_{\tau}} = \frac{\alpha_{\tau}}{\lambda_{\tau}} \cdot \left( \frac{y_{\tau}}{J_{\tau}} - 1 \right)$$

obs: note que, como esperado, 
$$E[T^d] = E[T^d] = 0$$

$$\nabla_{\tau} = \begin{pmatrix} \nabla_{\tau}^{\lambda} \\ \nabla_{\tau}^{\alpha} \end{pmatrix} = \begin{pmatrix} \ln(y_{\tau}) - \frac{1}{2t} \ln(x_{\tau}) - \frac{1}{2t} \ln(x_{\tau}) - \ln(x_{\tau})$$

$$I_{\tau/\tau-1} = E_{\tau-1} \left[ \nabla_{\tau}^{\alpha} \nabla_{\tau}^{'\alpha} \right] = E_{\tau-1} \left[ \nabla_{\tau}^{\alpha} \right]^{2} = E_{\tau-1} \left[ \nabla_{\tau}^{\alpha} \right]$$

$$I_{t/\tau-1} = E_{\tau-1} \left[ V_{\tau}^{1} V_{\tau}^{1} \right] = E_{\tau-1} \left[ V_{\tau}^{1} \right]^{2} = -E_{\tau-1} \left[ V_{\tau}^{1} \right]$$

$$I_{\tau/t-1}^{\alpha,1} = E_{\tau-1} \left[ \nabla_{\tau}^{1} \nabla_{\tau}^{\alpha} \right] = -E_{\tau-1} \frac{\partial}{\partial \alpha_{\tau}} \left[ \nabla_{\tau}^{1} \right] = -E_{\tau-1} \frac{\partial}{\partial \lambda_{\tau}} \left[ \nabla_{\tau}^{\alpha} \right]$$

$$\frac{G}{dt} = \begin{bmatrix} \Psi_2(d_t) \cdot 1/d_t & O \\ O & \alpha_t/d_t \end{bmatrix}$$

$$\begin{cases} h_1(\alpha_t) = \int_{1T} I & \ln \alpha_t = \int_{1T} \cos \alpha_t & \alpha_t = e^{\int_{1T} I} \int_{\alpha_t} \int_{r_t} \int_$$

E[yr/d, hr] = hr e V[yeld, hr] = hr/d

Parametrização fr = lm dr ;  $\Psi = \{lmd, lnk, lnke, l$