Optimal constant piecewise vaccination and lockdown policies for COVID-19

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Abstract

We formulate a controlled system of ordinary differential equations, with vaccination and lockdown interventions as controls, to simulate the mitigation of COVID-19. The performance of the controls is measured through a cost functional involving vaccination and lockdown costs as well as the burden of COVID19 quantified in DALYs. We calibrate parameters with data from Mexico City and Valle de Mexico. By using differential evolution, we minimize the cost functional subject to the controlled system and find optimal policies that are constant in time intervals of a given size. The main advantage of these policies relies on its practical implementation since the health authority has to make only a finite number of different decisions. Our methodology to find optimal policies is relatively general, allowing changes in the dynamics, the cost functional, or the frequency the policymaker changes actions.

Keywords: COVID-19, Optimal Control, COVAX, Vaccination, WHO-SAGE, DALYs.

1. Introduction

At the date of writing this manuscript, the USA is running its COVID-19 vaccination with Pfizer-BioNTech vaccine. This vaccine development along with Astra-Zeneca,Cansino, Sputnik V, Novavax among others' promise to deliver enough dosesfor Latin America. In Mexico, particularly, the first stock with around 40 000 shots has arrived past Christmas. In past October, WHO established a recommended protocol for prioritizing access to this pharmaceutical hope giving clear lines about who has to be vaccinated first and why. However, each developed vaccine implies different issues around its application. For example, Pfizer-BioNTech vaccine requires two doses and particular logistics requirements that demand special services. In Mexico, despite Pfizer-BioNTech has been taking the responsibility to capacitate personnel that manage the vaccination, there is an explicit demand for logistics resources that limit the institutions' response. On the hand, nonpharmaceutical interventions (NPIs), like a lockdown, also involve economic costs. Our research in this manuscript explores the effect of two interventions, vaccination and lockdown, to mitigate the propagation of COVID-19.

Among the related literature about the two interventions we deal with in this paper, we can mention the following. The problem of who is vaccinated first, when the number of available shots is limited, has been transformed into an optimal allocation problem of vaccine doses in [1, 2]. These articles give answers to the critical question of how much doses allocate to each different group according to risk and age to minimize the burden of COVID-19. In our study, we take the allocation for granted and consider only the vaccination rate.

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Further, papers modeling NPIs consider the diminish of contact rates—by reducing mobility—or modulating parameters regarding the generation of new infections by linear controls [3, 4], Lockdown–Quarantine [5], shield immunity [6]. In addition, Libotte et. al. reports in [7] optimal vaccination strategies for COVID-19.

Since health services' response will be limited by the vaccine stock and logistics costs, implementing in parallel NPIs is imminent. We focus on formulating and studying via simulation a Lockdown-Vaccination system by consider the vaccine recently approved by Mexico Health Council. We aim to design a schedule for dose application subject to a given vaccine stock that will be applied in a given period of time. For this purpose, we formulate an optimal control problem that minimizes the burden of COVID-19 in DALYs [8], the cost generated by running the vaccination campaign, and economic damages due to lockdown.

One of the main features of our model is that we consider piecewise constant control policies instead of general measurable control policies —also called permanent controls—to minimize a cost functional. General control policies are difficult to implement since the authority has to make different choices every permanently. The optimal policies we find are constant in each interval of time and hence these policies are easier to implement. To the best of our knowledge, our manuscript is the first optimal control model with both lockdown and vaccination strategies that are easy to implement in the sense described above.

In Section 2, we formulate the basic spread model for COVID19 and calibrate its parameters. Then, Section 3 establishes the lockdown–vaccination model and discusses the regarding reproductive number in Section 4. In Section 5 we describe the optimal control problem which consists in minimizing a cost functional subject to controlled lockdown–vaccination system. The optimal policies we find, by solving numerically the optimal control problem, are presented in Section 6. We conclude with some final comments in Section 7.

2. Covid-19 spread dynamics

We split a given population of size N in the basic SEIR structure with segregated classes according to the manifestation of symptoms. Let $L, S, E, I_S, I_A, H, R, D$ respectively denote the class of individuals according to their current state, namely

Lockdown (L) All individuals that have low or null mobility and remain under isolation. Thus individuals in this class reduce their contagion probability.

Suceptible (S) Individuals under risk

Exposed (E) Population fraction that hosts SARS-CoV-2 but cannot infect

Infected-Symptomatic (I_S) Population infected fraction with symptoms and reported as confirmed cases

Infected-Asymptomatic (I_A) Infected individuals with transitory or null symptoms and unreported

Hospitalized (H) Infected population that requires hospitalization or intensive care.

Recover or removed (R) Population that recovers from infection and develops partial immunity

Death (D) Population fraction that died due to COVID-19

To fit data of cumulative reported symptomatic cases, we postulate the counter state Y_{I_S} and make the following assumptions.

Assumptions 1. According to above compartment description, we made the following hypotheses.

(A-1) We suppose that at least 30 % of the population is locked down and a fraction of this class eventually moves to the susceptible compartment at rate δ_L.

(A-2) Force infection is defined as the probability of acquiring COVID-19 given the contact with a symptomatic or asymptomatic individual. Thus we normalize with respect to alive population population $N^\star$.

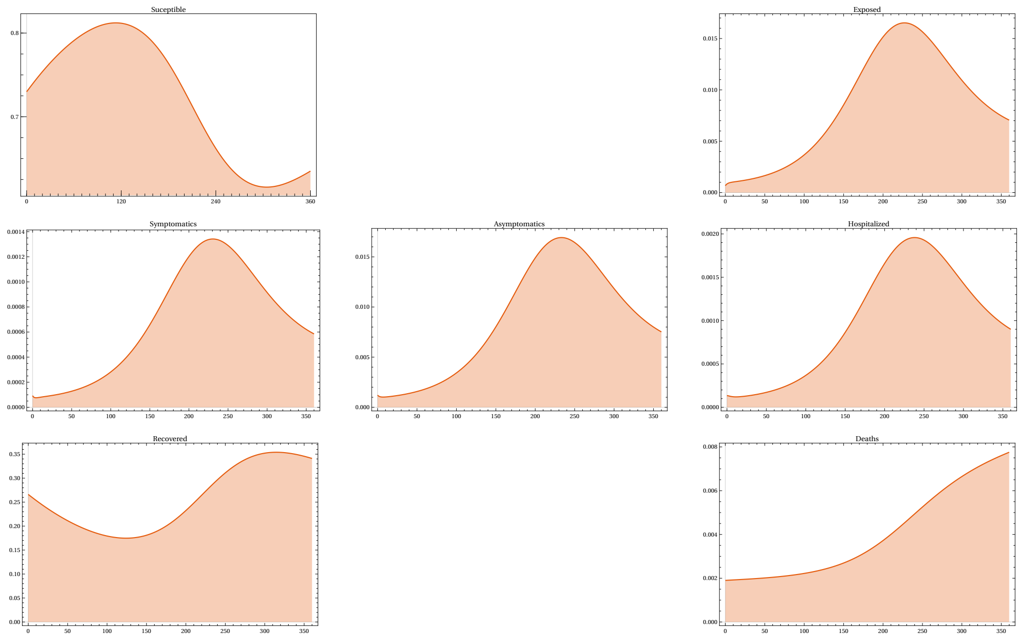

Figure 1: Spreed dynamics of COVID-19 according to model in Equation (1).

(A-3) Susceptible individuals become exposed—but not infectious—when they are in contact with asymptomatic or symptomatic individuals. Thus β_S and β_A denote the probabilities of being infectious given the contact with a symptomatic or asymptomatic infectious individuals, respectively.

(A-4) After a period of latency $1/\kappa = 5.1$ days, an exposed individual becomes infected. Being p the probability of developing symptoms and $(1-p)$ the probability of becoming infectious but asymptomatic. Thus $p\kappa E$ denotes the exposed individuals that become infectious and develop symptoms.

(A-5) Asymptomatic individuals do not die or stay in the Hospital.

(A-6) A fraction μ_H of symptomatic individuals dies due to COVID-19 without hospitalization.

Thus we formulate the following Ordinary Differential Equation (ODE)

$$\begin{aligned}
S' &= \mu N^\star + \delta_R R - (\lambda + \mu) S, \\
E' &= \lambda(\epsilon L + S) - (\kappa + \mu) E, \\
I_S' &= p\kappa E - (\gamma_S + \delta_H + \mu_{I_S} + \mu) I_S, \\
I_A' &= (1-p)\kappa E - (\gamma_A + \mu) I_A, \\
H' &= \delta_H I_S - (\gamma_H + \mu_H + \mu) H, \\
R' &= \gamma_S I_S + \gamma_A I_A + \gamma_H H - (\delta_R + \mu) R, \\
D' &= \mu_{I_S} I_S + \mu_H H, \\
\frac{dY_{I_S}}{dt} &= p\kappa E, \\
\lambda &:= \frac{\beta_A I_A + \beta_S I_S}{N^\star}, \\
N^\star(t) &= L + S + E + I_S + I_A + H + R.
\end{aligned} \tag{1}$$

See Table 1 for notation and references values. Put here the flow diagram

[SDIV 1] use WPS

Parameter	Description
μ	Death rate
β_S	Infection rate between susceptible and symptomatic infected
β_A	Infection rate between susceptible and asymptomatic infected
λ_V	Vaccination rate
δ_V^{-1}	Vaccine-induced immunity
ε	Vaccine efficacy
κ^{-1}	Average incubation time
p	New asymptomatic generation proportion
θ	Proportion of suceptible individuals under lockdown
γ_S^{-1}	Average time of symptomatic recovery
γ_A^{-1}	Recovery average time of asymptomatic individuals
γ_H^{-1}	Recovery average time by hospitalization
δ_R^{-1}	Natural immunity
δ_H	Infected symptomatic hospitalization rate

Table 1: Parameters definition of model in Equation (1).

2.1. Parameter calibration

Bayesian estimation. We calibrate parameters of our base dynamics (1) via Multichain Montecarlo (MCMC). To this end, we assume that the cumulative incidence of new infected symptomatic cases CI_S follows a Poisson distribution with mean $\lambda_t = IC_s(t)$. Further, following [] we postulate priors for p and κ

$$\begin{aligned} Y_t &\sim Poisson(\lambda_t), \\ \lambda_t &= \int_0^t p\delta_e E, \\ p &\sim \text{Uniform}(0.3, 0.8), \\ \kappa &\sim \text{Gamma}(10, 50). \end{aligned} \tag{2}$$

Figure 2 displays data of cumulative confirmed cases of COVID-19 in Mexico city, and Figure 3 displays the fitted curve of our model in Equations (1) and (2). Table 2 encloses estimated parameters to this setting.

[SDIV 2] Review this R_0 calculation with Gabriel

Parameter	Median	Reference
q_r, ϵ	0.4, 0.3, 0.1	this study
β_S	$q_r \times 8.690\,483 \times 10^{-1}$	this study
β_A	$q_r \times 7.738\,431 \times 10^{-1}$	this study
κ	0.196 078 43	$*$
p	0.1213	$*$
θ	0.2,	this study
δ_L	0.04	postulated
δ_H	0.2	$*$
δ_V	0.002 739 726 027 397 260 3	$\delta_V^{-1} = 2\,\text{years}$ CanSinoBIO
δ_R	0.005 555 56	$\delta_R^{-1} \approx 180\,\text{days}$
μ	$3.913\,894 \times 10^{-5}$	$**$
μ_{I_S}	0.0	
μ_H	0.016 32	[9]
γ_S	0.092 506 94	$*$
γ_A	0.167 504 19	$*$
γ_H	$5.079\,869 \times 10^{-1}$	$*$
λ_V	0.000 611 35	
ε	0.7, 0.80, 0.9, 0.95	[PRESS RELESASES]
N	26 446 435	$**$
L_0	0.266 260 097 021 127 96	
S_0	0.463 606 046 009 872	
E_0	0.000 670 33	$*$
I_{S_0}	9.283×10^{-5}	$***$
I_{A_0}	0.001 209 86	$*$
H_0	$1.341\,579\,69 \times 10^{-4}$	$**$
R_0	$2.661\,259\,39 \times 10^{-1}$	
D_0	0.001 900 74	$**$
X_{vac}^0	0.0	
V_0	0.0	
$Y_{I_S}^0$	0.122 581 64	
B	0.000 359 216 658 124 242 5	$9500\,\text{beds}/N$
a_{I_S}	0.002 012 775 543 825 648 6	DALY def
a_H	0.001 411 888 738 103 725, or $a_H(x) := 0.001\,411\,888\,738\,103\,725 \log(\frac{1}{B-\kappa I_S})$	DALY def [Jo 2020]
a_D	7.25	DALY def

Table 2: Model parameters. Values based mainly in [FNEG]

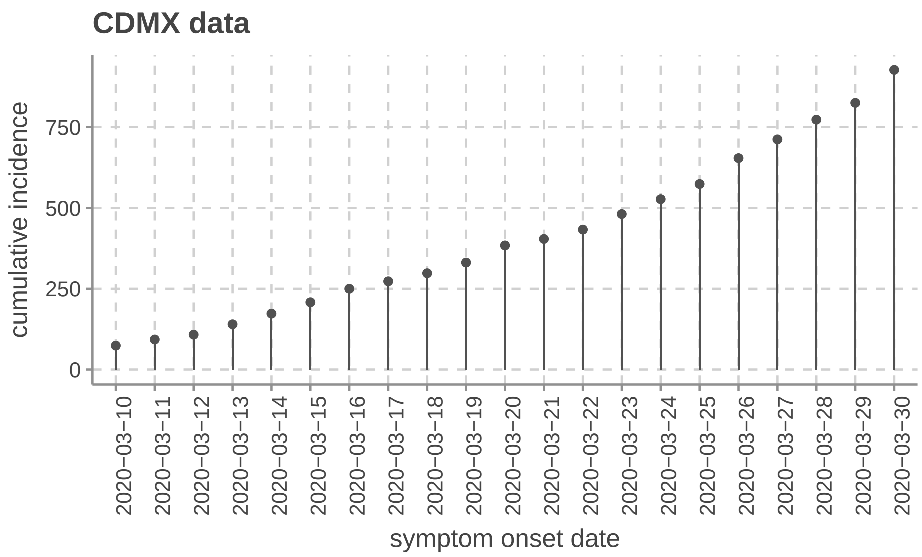

Figure 2: Cumulative new symptomatic and confirmed COVID19 reported cases from Ciudad de Mexico and Valle de Mexico [?] between March, 10, to March 30 of 2020. https://plotly.com/ AdrianSalcedo/48/

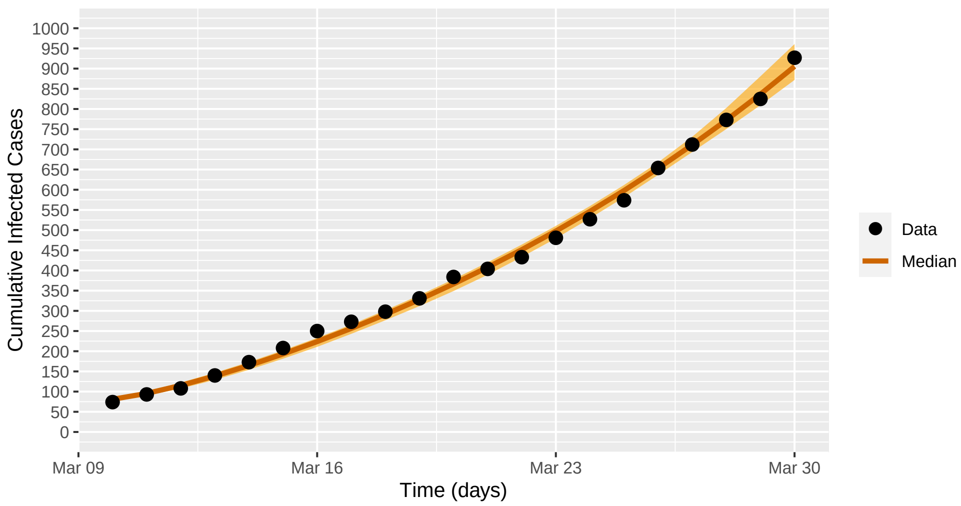

Figure 3: Fit of daily new cases of Mexico city during exponential growth. https://plotly.com/ AdrianSalcedo/50/

3. Imperfect-preventive COVID-19 vaccination

Assumptions 2. According to COVID-19 dynamics in model in Equation (1), we made the following modeling hypotheses about the regarding vaccine.

(VH-1) Vaccine is preventive and only reduce susceptibility.

[SDIV 3] Justify this hypothesis cite

(VH-2) The vaccination camping omits testing to detect seroprevalence. Thus Expoxed, Infected Asymptomatics and Recovered Asymptomatic individuals are undetected but would obtain a vaccine dose —which in these model represent a waste of resources

(VH-3) Individuals under Lockdown also would be vaccinated

(VH-4) The vaccine is leaky and with efficacy $\epsilon \in [0.7, .975]$

(VH-5) Vaccine induced immunity last 2 years

(VH-6) Natural immunity last a period of 180 days

$$
\begin{aligned}
L' =& \theta\mu N^{\star} - (\epsilon\lambda + \delta_L + \lambda_V + \mu)L \\
S' =& (1-\theta)\mu N^{\star} + \delta_L L + \delta_V V + \delta_R R \\
& - (\lambda + \lambda_V + \mu)\, S \\
E' =& \lambda(\epsilon L + (1-\varepsilon)V + S) - (\kappa + \mu)E \\
I_S' =& p\kappa E - (\delta_H + \gamma_S + \mu_{I_S} + \mu)I_S \\
I_A' =& (1-p)\kappa E - (\gamma_A + \mu)I_A \\
H' =& \delta_H I_S - (\gamma_H + \mu_H + \mu)H \\
R' =& \gamma_S I_S + \gamma_A I_A + \gamma_H H - (\delta_R + \mu)R \\
D' =& \mu_{I_S} I_S + \mu_H H \\
V' =& \lambda_V (S + L) - [(1-\varepsilon)\lambda + \delta_V + \mu]\, V
\end{aligned}
$$

$$
\begin{aligned}
\frac{dX_{vac}}{dt} &= (u_V(t) + \lambda_V)\,[L + S + E + I_A + R] \\
\frac{dY_{I_S}}{dt} &= p\kappa E \\
\lambda &:= \frac{\beta_A I_A + \beta_S I_S}{N^{\star}}
\end{aligned}
\tag{3}
$$

$$
\begin{aligned}
L(0) &= L_0,\ S(0) = S_0,\ E(0) = E_0, \\
I_S(0) &= I_{S_0}, I_A(0) = I_{A_0}, H(0) = H_0, \\
R(0) &= R_0,\ D(0) = D_0, \\
V(0) &= 0,\ X_{vac}(0) = 0, \\
X_{vac}(T) &= x_{coverage}, \\
N^{\star}(t) &= L + S + E + I_S + I_A + H + R + V.
\end{aligned}
$$

4. Lockdown-Vaccination reproductive number

The basic reproductive number, which is generally denoted by R_0, is a threshold quantity with which we can use particular control strategies. The epidemiological interpretation of R_0 is the average number of secondary cases produced by an infected individual introduced into a population of susceptible individuals. Using Van DenDrishe's [10] definition of reproductive number we obtain

$$R_0 := \frac{\kappa}{(\kappa+\mu)(\delta_L+\mu)}\left(\mu R_1+\delta_L\right)\left[\frac{p\beta_S}{R_2}+\frac{(1-p)\beta_A}{\gamma_A+\mu}\right],$$

where

$$R_1 = 1-\theta(1-\epsilon),$$
$$R_2 = \mu+\delta_H+\gamma_S+\mu_{I_S}.$$

The factor $\frac{p\beta_S}{R_2}$ measures the proportion of new infections generated by a symptomatic infectious individual in the time that it lasts infected. In a similar way, the factor $\frac{(1-p)\beta_A}{\gamma_A+\mu}$ measures the new infections generated by an asymptomatic infectious individual in the time that it lasts infected. The factor $\frac{\mu R_1+\delta_L}{\delta_L+\mu}$ measures the number of individuals in lockdown that leave the lockdown, which can be infected. And finally, the factor $\frac{\kappa}{\kappa+\mu}$ measures the time of the disease's incubation. If we consider that there is no lockdown, we have that R_0 is reduced to

$$\tilde{R}_0 := \frac{\kappa}{(\kappa+\mu)}\left[\frac{p\beta_S}{R_2}+\frac{(1-p)\beta_A}{\gamma_A+\mu}\right].$$

Note that we have the relation $R_0 \leq \tilde{R}_0$. These indicate that there is greater transmission of the disease if there is no lockdown. Here Gabriel's R not calculations.SDIV Considering assumptions 2, we can establish a vaccine reproductive number, in which individuals who have already been vaccinated can become infected individuals by being in contact with the symptomatic infected. Using Van den Driessche's [10] definition of reproductive number and [11], we obtain

[SDIV 4] Here counto plots figure as function of efficacy and vaccina tion rate

$$R_0^V := \left[1-\frac{\varepsilon\lambda_V}{\mu+\lambda_V+\delta_V}-\frac{\theta\mu(1-\epsilon)}{\mu+\delta_L+\lambda_V}\right](\mu R_1+\delta_L)R_0.$$

The threshold quantity R_0^V is the reproductive number of infection which can be interpreted as the number of infected people produced by one infected individual introduced into the population in the presence of vaccination.

[1] edit plot range to dis play level RV=1

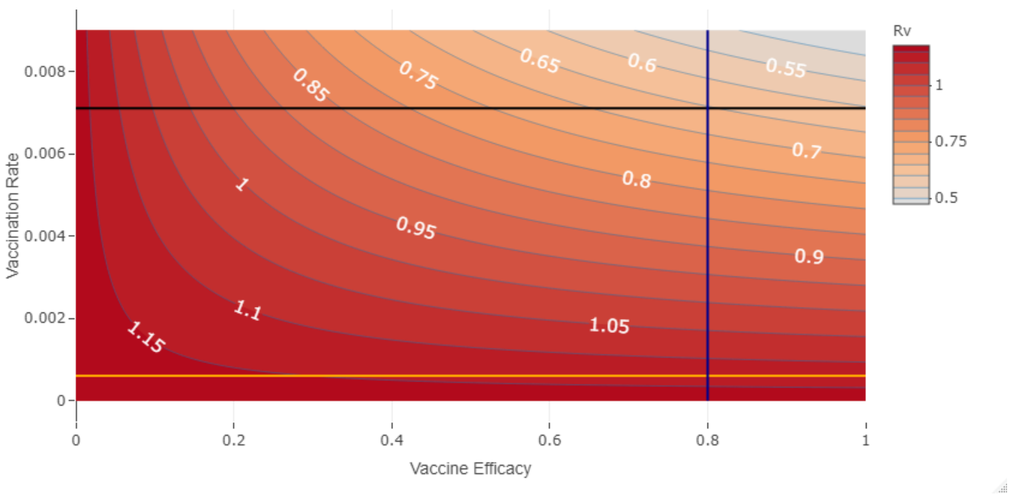

Figure 4: Contour plot of R_0^V as a function of ϵ and λ_V and vaccine-induced immunity average time of half year. orange line represents the value of $\lambda_{V base} = 0.000\,611$, corresponding to a coverage $x_{coverage} = 0.2$ and a horizon time $T = 365$ days. Intersection of black line and blue line show a scenario in which it is possible to have the $R_V = 0.65$, considering a vaccine efficacy of 0.8 and a vaccination rate of 0.7.

shows the efficacy of the vaccine as a function of the vaccination rate. The blue line, $\varepsilon = 0.8$, tells us what value of λ_V to take for which to have the level curve where $R_0^V < 1$. In the gray region of the figure 5,

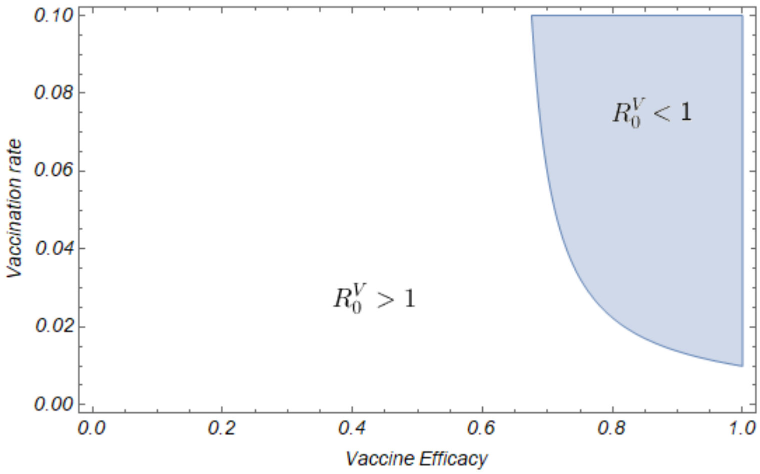

Figure 5: Vaccine efficacy versus vaccination rate feasibility. In the gray shaded region $R_V < 1$ and in the white region $R_V > 1$. Note that, for our scenario, we consider no lockdown individuals. https://plotly.com/ AdrianSalcedo/52/

you can see the values of vaccine efficacy and vaccination rate for which $R_0^V < 1$. In this figure, we consider that the lockdown effect is not present. If we take $\varepsilon = 0.2$, we can see that we always have $R_0^V > 1$ with which choice of λ_V.

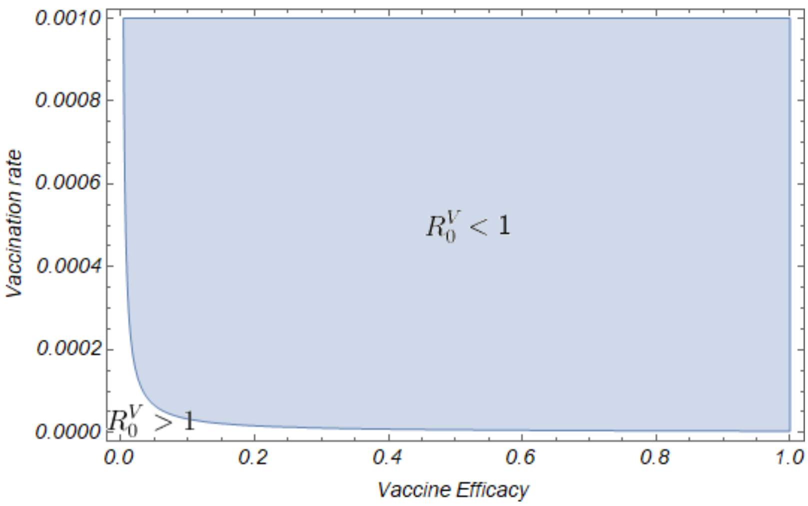

Figure 6: Vaccine efficacy versus vaccination rate feasibility. In the gray shaded region $R_V < 1$ and in the white region $R_V > 1$. Note that, for our scenario, we consider lockdown individuals. https://plotly.com/ AdrianSalcedo/54/

In thefigure 6, we take into account that the lockdown effect is present. We can see that the gray region, $R_0^V < 1$, is much larger than in the figure. Note that we can choose smaller values for ε and λ_V when we do have an individual lockdown.

5. Optimal controlled version

Controlled Model. Now wee model vaccination, treatment and lockdown as a optimal control problem. According to dynamics in Equation (1), we modulate the vaccination rate with a time-dependent control signal $u_V(t)$. We add compartment X_{vac} to count all the vaccine applications of lockdownm susceptible, exposed, asymptomatic and recovered individuals. This process is modeled by

$$X'(t) = (\lambda_V + u_V(t))(L + S + E + I_A + R) \tag{4}$$

and describes the number of applied vaccines at time t. Consider

$$x(t) := (L, S, E, I_S, I_A, H, R, D, V, X_{vac})^\top(t)$$

and control signal $u_v(\cdot)$. We quantify the cost and reward of a vaccine strategy policy via the penalization functional

$$J(u_L, u_V) := \int_0^T a_S p\kappa E(r) + a_H \delta_H I_s(r) + a_D\left[\mu_{I_S} I_S(r) + \mu_H H(r)\right] + \frac{1}{2}\left[c_L u_L^2(r) + c_V u_v^2(r)\right] dr. \tag{5}$$

In other words, we assume in functional J that pandemic cost is proportional to the symptomatic hospitalized and death reported cases and that a vaccination and lockdown policies implies quadratic consumption of resources.

[SDIV 5] Write expli- cation in th context of DALYs

Further, since we aim to simulate vaccination policies at different coverage scenarios, we impose the vaccination counter state's final time condition $X_{vac}(T)$

$$\begin{aligned} x(T) &= (\cdot, \cdot, \cdot, \cdot, \cdot, X_{vac}(T))^\top, \in \Omega \\ X_{vac}(T) &= x_{coverage}, \\ x_{coverage} &\in \{\mathrm{Low}(0.2), \mathrm{Mid}(0.5), \mathrm{High}(0.8)\}. \end{aligned} \tag{6}$$

Thus, given the time horizon T, we impose that the last fraction of vaccinated populations corresponds to 20%, 50% or 80%, and the rest of final states as free. We also impose the path constraint

$$\Phi(x, t) := H(t) \leq B, \qquad \forall t \in [0, T], \tag{7}$$

to ensure that healthcare services will not be overloaded. Here κ denotes hospitalization rate, and B is the load capacity of a health system.

Given a fixed time horizon and vaccine efficiency, we estimate the constant vaccination rate as the solution of

$$x_{coverage} = 1 - \exp(-\lambda_V T). \tag{8}$$

That is, λ_V denotes the constant rate to cover a fraction $x_{coverage}$ in time horizon T. Thus, according to this vaccination rate, we postulate a policy u_v that modulates vaccination rate according to λ_V as a baseline. That is, optimal vaccination amplifies or attenuates the estimated baseline λ_V in a interval $[\lambda_V^{\min}, \lambda_V^{\max}]$ to optimize functional $J(\cdot)$—minimizing symptomatic, death reported cases and optimizing resources.

Our objective is minimize the cost functional (5)—over an appropriated functional space—subject to the dynamics in equations (1) and (4), boundary conditions, and the path constrain in (7). That is, we search for vaccination policies $u_V(\cdot)$, which solve the following optimal control problem (OCP).

$$
\begin{aligned}
\min_{\mathbf{u}\in\mathcal{U}} J(u_L, u_V) := & \int_0^T a_S p\kappa E(r) + a_H \delta_H I_s(r) + a_D \left[\mu_{I_S} I_S(r) + \mu_H H(r)\right] dr + \\
& \int_0^T \frac{1}{2}\left[c_L u_L^2(r) + c_V u_v^2(r)\right] dr. \\
\text{s. t.} & \\
L' &= \theta\mu N^\star - \epsilon\lambda L - u_L(t)L - \mu L \\
S' &= (1-\theta)\mu N^\star + u_L(t)L + \delta_v V + \delta_R R \\
& \quad - \left[\lambda + (\lambda_V + u_V(t)) + \mu\right] S \\
E' &= \lambda(\epsilon L + (1-\varepsilon)V + S) - (\kappa + \mu)E \\
I_S' &= p\kappa E - (\gamma_S + \mu_{I_S} + \delta_H + \mu)I_S \\
I_A' &= (1-p)\kappa E - (\gamma_A + \mu)I_A \\
H' &= \delta_H I_S - (\gamma_H + \mu_H + \mu)H \\
R' &= \gamma_S I_S + \gamma_A I_A + \gamma_H H - (\delta_R + \mu)R \\
D' &= \mu_{I_S} I_S + \mu_H H \\
V' &= (\lambda_V + u_V(t))S - \left[(1-\varepsilon)\lambda + \delta_V + \mu\right] V
\end{aligned}
\tag{9}
$$

$$
\begin{aligned}
\frac{dX_{vac}}{dt} &= (u_V(t) + \lambda_V)\left[L + S + E + I_A + R\right] \\
\frac{dY_{I_S}}{dt} &= p\kappa E \\
\lambda &:= \frac{\beta_A I_A + \beta_S I_S}{N^\star}
\end{aligned}
$$

$$
\begin{aligned}
L(0) &= L_0,\ S(0) = S_0,\ E(0) = E_0,\ I_S(0) = I_{S_0}, \\
I_A(0) &= I_{A_0}, H(0) = H_0,\ \ R(0) = R_0,\ D(0) = D_0, \\
V(0) &= 0,\ X_{vac}(0) = 0, \quad u_V(.) \in [u_{\min}, u^{\max}], \\
X_{vac}(T) &= x_{coverage}, \quad \kappa I_S(t) \leq B, \qquad \forall t \in [0,T], \\
N^\star(t) &= L + S + E + I_S + I_A + H + R + V
\end{aligned}
$$

The policies we are considering in the OCP are piecewise constant; see the Appendix for details. OCPs with this class of policies have been studied in different contexts. For instance, a solution method based on the gradient of the cost functional is studied in [12]; convergence results of piecewise constant solutions to permanent solutions in linear-quadratic problems are given in [13]; or, in [14], a general numerical methodology to find piecewise constant solutions is proposed. In fact, to find the optimal policies we use the methodology [14]. Even though the existence of solutions to OCPs in the class of piecewise constant policies is known, for completeness, we sketch a straightforward proof in the Appendix under assumptions that hold for the OCP described above.

6. Numerical Experiments

6.1. Methodology

We simulate and scenario corresponding to a hypothetical but plausible initial conditions and parameters. We integrate model in **??** by classic Runge Kutta scheme and solve the optimization stage with the so called Differntial Evolution method. Differential Evolution (DE) [15] is an evolutionary algorithm successfully

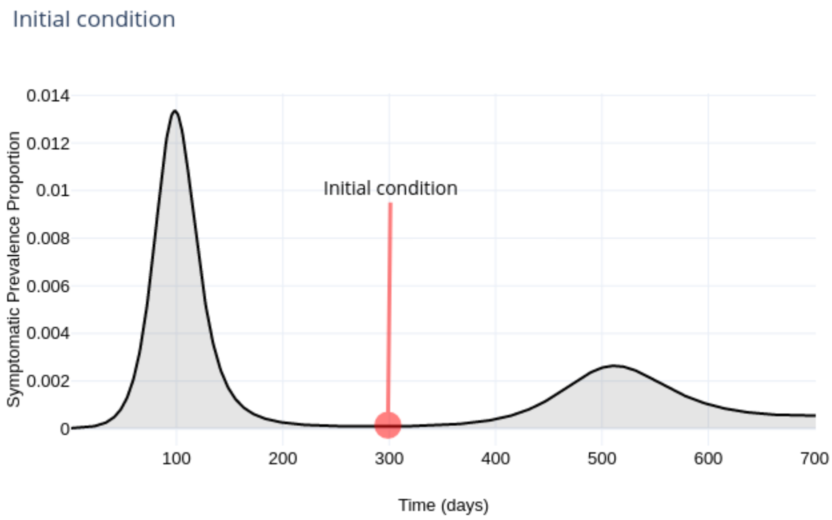

Figure 7: Initial condition scheme. We assume a positive prevelance. Forreference, at the date of write this manuscript, prevalence in CDMX is around 16 000 cases, see https://plotly.com/ sauld/36/ to display a electronic viewer.

employed for global optimization [16]. The method is designed to optimize functions $f : \mathbb{R}^n \to \mathbb{R}$. Nevertheless, DE can be applied to optimize a functional as stated in [14]. The method can be coded following Algorithm 1, where an initial random population on the search space $\mathcal{V}$ of size N_p is subjected to mutation, crossover and selection. After this process a new population is created which, again would be subjected to the evolutionary process. This process is repeated until some stopping criteria is fulfilled. Finally the best individual (according to some objective function f_{ob} to optimize) is extracted. These operations are conducted by the operators $\mathbf{X}_0$, $\mathbf{M}$, $\mathbf{C}$, $\mathbf{S}$, $\mathbf{x}_{best}$; whose explicit form are coded in [17].

In the optimization of this study the mutation scale factor F and the crossover probability C_r were taken as 1 and 0.3 respectively, additional N_p has been taken as 4 times the number of parameters (the dimension of the vector used to describe the two controls—see [14]), which in our case was of 180. As stopping criteria we have used a maximum number of generations which is taken as 5000.

We provide in [**?**] a GitHub repository with all regarding R and Fortran sources for the sake of reproductivity. This repository also encloses data sources and a Wolfrang Mathematica notebook to reproduce all reported figures.

Algorithm 1 Differential Evolution Algorithm

$X \leftarrow \mathbf{X}_0(Np, \mathcal{V})$
while (the stopping criterion has not been met) **do**
  $M \leftarrow \mathbf{M}(X, F, \mathcal{V})$
  $C \leftarrow \mathbf{C}(X, M, C_r)$
  $X \leftarrow \mathbf{S}(X, C, f_{ob})$
end while
$\mathbf{x}_{best} \leftarrow \mathbf{Best}(X, f_{ob})$

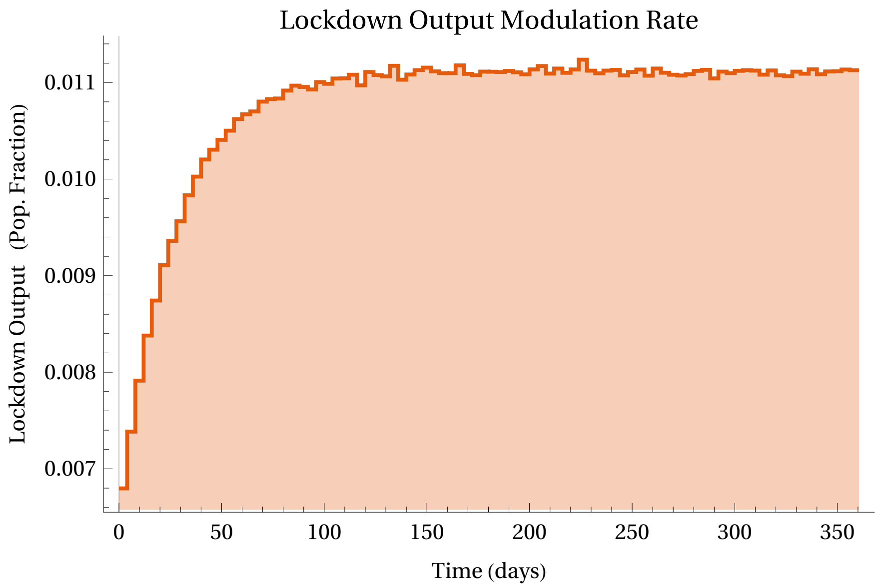

Figure 8: Lockdown modulation signal. https://plotly.com/ AdrianSalcedo/56/ to display a electronic viewer.

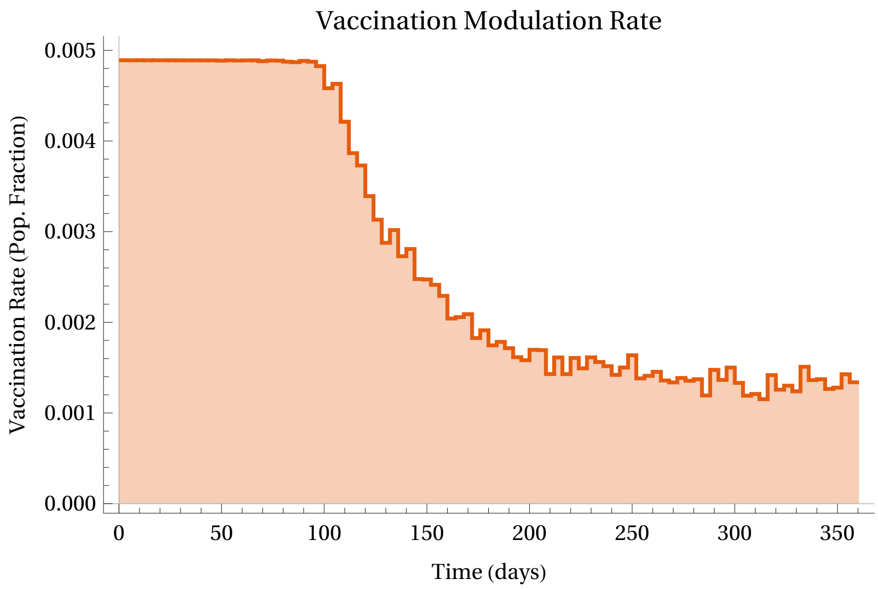

Figure 9: Vaccination rate modulation. https://plotly.com/ AdrianSalcedo/58/

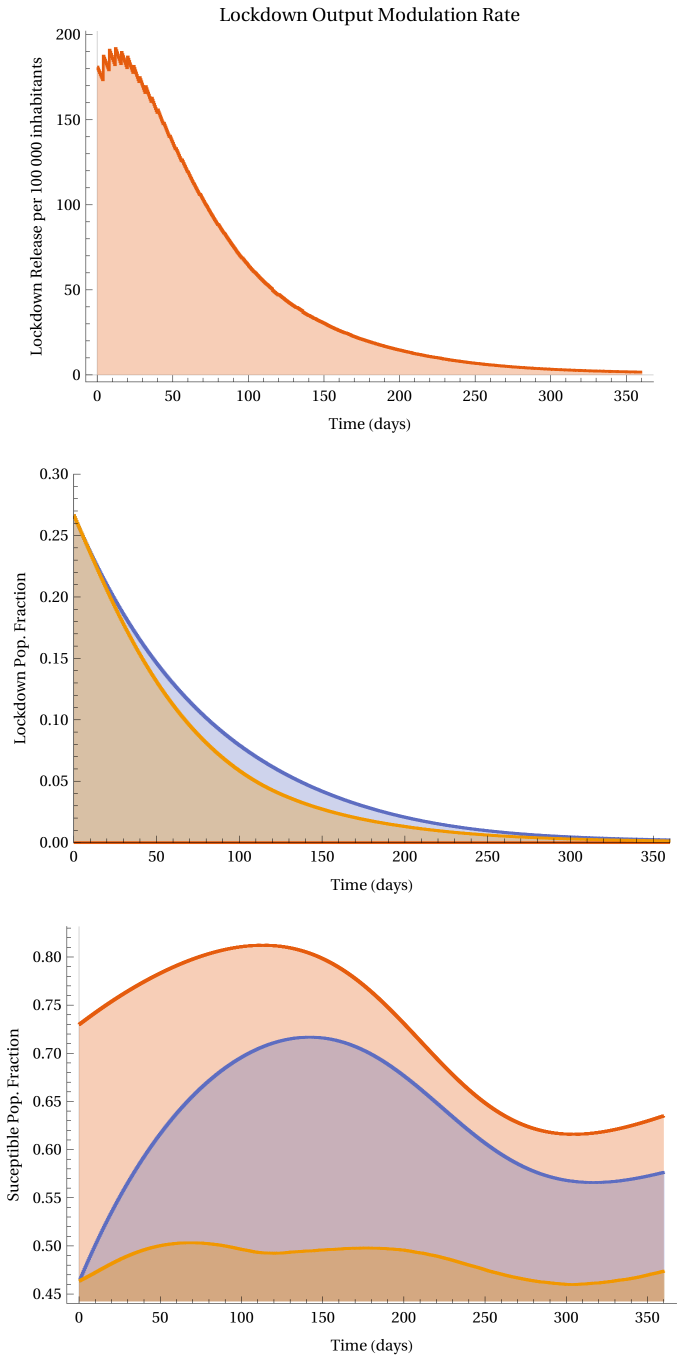

Figure 10: Modulation lock down release. https://plotly.com/ AdrianSalcedo/60/

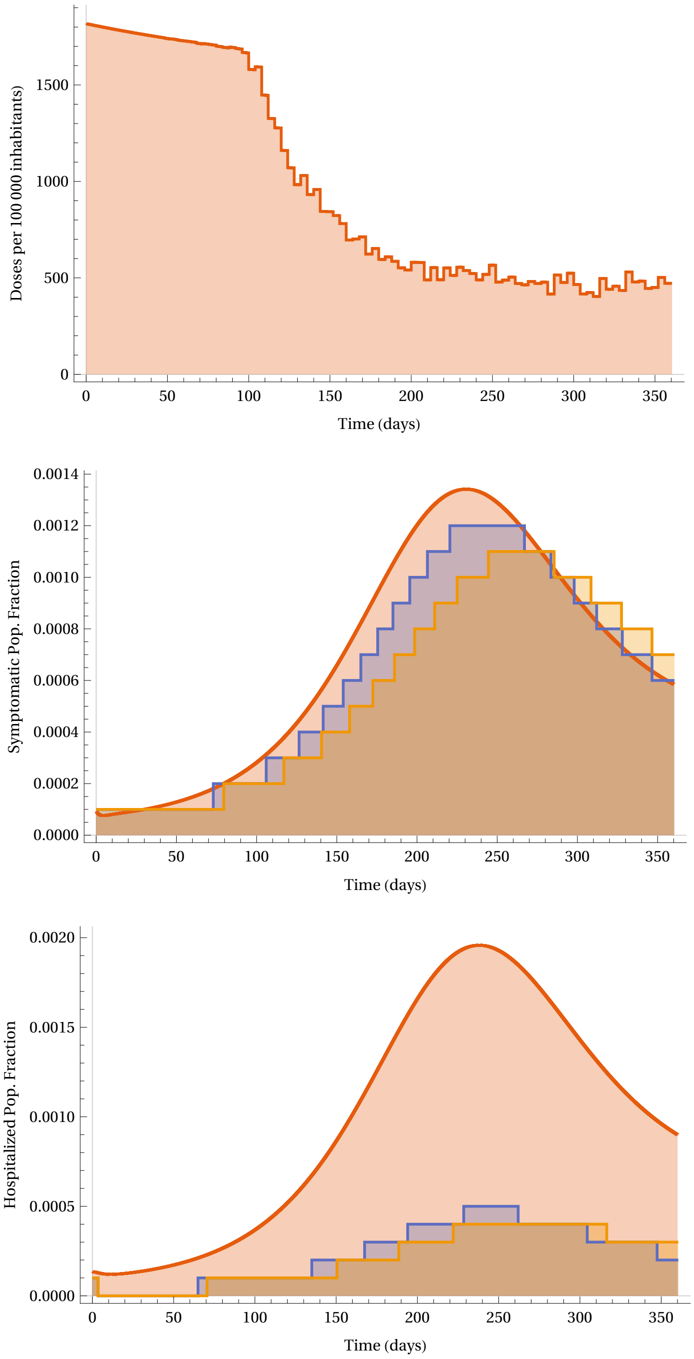

Figure 11: Symptomatic Prevalence and Hozpitalization. https://plotly.com/ AdrianSalcedo/61/

7. Conclusion

Changes (compact)

Author: anonymous

Commented 1

Author: SDIV

Added 2

Commented 5

Appendix A. Existence of optimal policies

In this appendix, we show the existence of optimal policies in the class of *piecewise constant policies*. Consider the following cost functional that we want to minimize

$$\int_0^T C(X(t), u(t))dt \tag{A.1}$$

subject to the dynamics

$$\dot{X}(t) = f(X(t), u(t)), \qquad 0 \le t \le T, \tag{A.2}$$

and the initial state $X(0) = x_0$. The functions $u : [0, T] \to U$ are called *control polices*, where U is a subset of some Euclidean space. Let $t_0 < t_1 < \ldots < t_n$, with $t_0 = 0$ and $t_n = T$, be a partition of the interval $[0, T]$. We consider piecewise constant policies $\tilde{u}$ of the form

$$\tilde{u}(t) = a_j \qquad t_j \le t < t_{j+1} \tag{A.3}$$

for $j = 0, \ldots, n-1$.

Assumptions 3. We made the following assumptions.

(A-1) The function f in the dynamics (A.2) is of class C^1.

(A-2) The cost function C in (A.1) is continuous and the set U is compact.

By Assumption (A-1), the system

$$\dot{X}(t) = f(X(t), a_0), \quad X(0) = x_0, \qquad 0 \le t \le t_1,$$

has a unique solution $\tilde{X}_0(t; x_0, a_0)$ which is continuous in (x_0, a_0); see, for instance [18]. Next, put $x_1 := \tilde{X}_0(t_1; x_0, a_0)$ and consider the system

$$\dot{X}(t) = f(X(t), a_1), \quad X(t_1) = x_1, \qquad t_1 \le t \le t_2,$$

Again, by Assumption (A-1), the latter system has a unique solution $\tilde{X}_1(t; x_1, a_1)$ which is continuous in (x_1, a_1). By following this procedure, we end up having a recursive solution

$$\begin{aligned} &\tilde{X}_{n-1}(t; x_{n-1}, a_{n-1}), \qquad t_{n-1} \le t \le T, \\ &x_{n-1} := \tilde{X}_{n-2}(t_{n-1}; x_{n-2}, a_{n-1}), \end{aligned}$$

where $\tilde{X}_{n-1}$ is continuous in (x_{n-1}, a_{n-1}).

For a control $\tilde{u}$ of the form (A.3) and the corresponding solution path $\tilde{X}$, we have

$$\int_0^T C(\tilde{X}(t), \tilde{u}(t))dt = \sum_{j=0}^{n-1} \int_{t_j}^{t_{j+1}} C(\tilde{X}_j(t), a_j)dt.$$

Notice that each $\tilde{X}_j$ is a continuous function of $(a_0, \dots, a_j)$ and x_0.

By Assumption (A-2), the mapping

$$(a_0, \dots, a_{n-1}) \mapsto \sum_{j=0}^{n-1} \int_{t_j}^{t_{j+1}} C(\tilde{X}_j(t), a_j) dt$$

is continuous. Since each piecewise constant policy $\tilde{u}$ of the form (A.3) can be identified with the vector $(a_0, \dots, a_{n-1})$ in the compact set $U \times \cdots \times U$, the functional (A.1) attains its minimum in the class of piecewise constant policies.

The cost functional (5) and the dynamics (1) are particular cases of (A.1) and (A.2), respectively, and satisfy Assumptions (A-1) and (A-2). Then there exists an optimal vaccination policy of the form (A.3).

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