

Advanced Macroeconomics II

Handout 4 - Optimization

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Short recap

Prototypical DP problem:

$$\begin{aligned} V(k, z) &= \max_{\{c, k'\}} u(c) + \beta E \left[V(k', z') | z \right] \\ \text{s.t. } c + k' &= f(k, z) \\ z' &= h(z, \eta); \eta \text{ stochastic} \end{aligned}$$

- ▶ We are looking for functions $\mathbf{V}, \mathbf{g}^c, \mathbf{g}^k$: We cannot solve this

We need to solve an approximate problem:

1. Discretize state space (functions are now vectors)
2. Approximate continuous function: **Interpolation**
 - ▶ Requires “exact” solution of maximization problem: **Optimization**

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- ▶ Local optimizers vs Global optimizers

Root finding:

- ▶ We can solve the problem by looking at the FOC (Euler equation)
- ▶ We are looking for values that make the FOC be zero (hence the root)

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2. Guess a solution (say a value for $\{c, k', \ell, \dots\}$)
3. Evaluate the objective function in that solution
4. Update your guess if needed

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★ We do have to help our optimizer with an initial guess of the solution

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★ Evaluating the function is the key step

- ▶ Evaluating might require solving intermediate problems (c vs ℓ)
- ▶ Requires evaluation in points off the grid (interpolation)
- ▶ Requires taking expectations (we are not there yet)

Optimization - Packages

- ▶ A good overview in quantecon ([click here](#))
- ▶ Native Julia optimization module (Optim.jl)
- ▶ Wrapper for C's NLOpt functions (NLOpt.jl)
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Ultimate source of all knowledge:

- ▶ Numerical Recipes: The Art of Scientific Computing by Press, Teukolki, Vetterling and Flannery

Local Optimizers

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- ▶ Local optimizers are generally faster than global methods
 - ▶ Drawback: We need to be “close to the solution”
- ▶ To overcome drawback we invest in **bracketing the solution**
 - ▶ Bracketing with theory: steady state convergence, minimum consumption, time constraints
 - ▶ Numerical procedures (see section 10.1 of Numerical Recipes)

Warning

We want to maximize... but computer scientists always want to minimize

- ▶ Make sure to operate on the negative of your value function
- ▶ Be careful! Most early bugs in your code are a misplaced minus sign

Bracketing a minimum (in one dimension)

- ▶ A minimum is bracketed by three points: a , b , and c
 - ▶ Without loss we will have: $a < b < c$
- ▶ A minimum is bracketed if: $f(a), f(c) > f(b)$

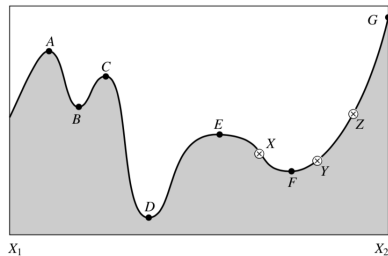


Figure 10.0.1. Extrema of a function in an interval. Points A , C , and E are local, but not global maxima. Points B and F are local, but not global minima. The global maximum occurs at G , which is on the boundary of the interval so that the derivative of the function need not vanish there. The global minimum is at D . At point E , derivatives higher than the first vanish, a situation which can cause difficulty for some algorithms. The points X , Y , and Z are said to “bracket” the minimum F , since Y is less than both X and Z .

Bracketing a minimum

Theory:

- ▶ We know that $c^* \in [\epsilon, f(k, z) - \underline{k}]$ for some $\epsilon, \underline{k} > 0$
- ▶ We know some problems are globally convergent so:
 - ▶ If $k \leq k_{ss}$ then $k'^* \in [k, k_{ss}]$, otherwise $k'^* \in [k_{ss}, k]$

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Numerically:

- ▶ Start with some “arbitrary” interval $[a, b]$
- ▶ Get c so as to get $b \in [a, c]$ (be smart in choosing c , read NR)
- ▶ Check if $f(a), f(c) > f(b)$
- ▶ Rinse and repeat

One-dimensional optimizers

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How do optimizers work?

- ▶ Bisection (Golden section)
- ▶ Parabolic interpolation (Brent)
 - ▶ Parabolic interpolation with derivative (dBrent)
- ▶ Higher polynomials (Do not use!)

Golden section

- ▶ Start with $a < b < c$ so that $f(a), f(c) > f(b)$
- ▶ Choose a point in $x \in [a, b]$ or $x \in [b, c]$, say you picked $x \in [b, c]$
- ▶ Keep x if $f(c), f(b) > f(x)$, x is the new candidate for a min

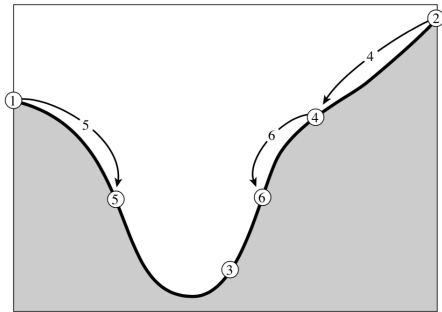


Figure 10.1.1. Successive bracketing of a minimum. The minimum is originally bracketed by points 1,3,2. The function is evaluated at 4, which replaces 2; then at 5, which replaces 1; then at 6, which replaces 4. The rule at each stage is to keep a center point that is lower than the two outside points. After the steps shown, the minimum is bracketed by points 5,3,6.

Golden section - How to pick intermediate point x ?

- ▶ We can write b as a convex combination of a and c

$$b = (1 - \gamma) a + \gamma c$$

Note: $\frac{b-a}{c-a} = \gamma$ and $\frac{c-b}{c-a} = 1 - \gamma$

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- ▶ We want to place x an additional $\eta(c - a)$ beyond b : $(x-b)/(c-a) = \eta$
- ▶ Two options for new segment: $[a, x]$ or $[b, c]$
 - ▶ First segment will have length $(\gamma + \eta)|c - a|$, second $(1 - \gamma)|c - a|$
 - ▶ If we want to min worst case (having too large of an interval)

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- ▶ Magic! x is symmetric to b ! Note: $|b - a| = |c - x|$
 - ▶ For $\eta > 0$ we need to place x in the longest of $[a, b]$ or $[b, c]$

Golden section - How to pick ratio γ ?

- ▶ If we use the same γ for all iterations this imposes *scale similarity*:

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$$\gamma = \frac{3 - \sqrt{5}}{2} \quad 1 - \gamma = \frac{1 + \sqrt{5}}{2} - 1 = \frac{1}{\text{Golden Ratio}} \approx 0.618$$

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- ▶ Golden section guarantees that each new function evaluation will bracket min to an interval $\frac{1}{\varphi}$ the size of the preceding interval.

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Question is not why, but when!

- ▶ When facing complicated problems is good to start with robust methods
- ▶ Start with golden section and then move to more complex method
- ▶ Stop early when $|a - c| < \text{tol}$ for some “large” tol .

(Inverse) Parabolic interpolation - Brent

- ▶ Basic idea is that a function can be locally parabolic (quadratic)
- ▶ We can use the formula for the abscissa x that is the minimum of a parabola to guess our new point (if function is actually quadratic we are done in one step!)

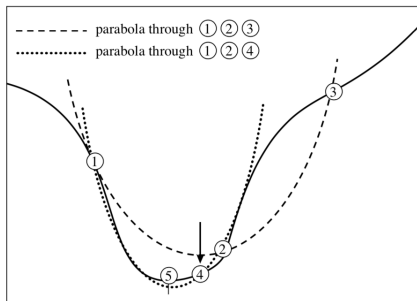


Figure 10.2.1. Convergence to a minimum by inverse parabolic interpolation. A parabola (dashed line) is drawn through the three original points 1,2,3 on the given function (solid line). The function is evaluated at the parabola's minimum, 4, which replaces point 3. A new parabola (dotted line) is drawn through points 1,4,2. The minimum of this parabola is at 5, which is close to the minimum of the function.

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Brent can be improved with derivatives:

- ▶ The sign of $f'(b)$ indicates only whether the next test point should be taken in the interval (a, b) or in the interval (b, c) .
- ▶ Avoids using derivatives in problematic ways

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“Once superlinear convergence sets in, it hardly matters whether its order is moderately lower or higher. [...] most function evaluations are spent in getting globally close enough to the minimum [...] we are more worried about all the funny “stiff” things that high-order polynomials can do, and about their sensitivities to roundoff error.”

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- ▶ Also general problems with derivatives in the computer:
“too many functions whose computed “derivatives” don’t integrate up to the function value and don’t accurately point the way to the minimum, usually because of roundoff errors, sometimes because of truncation error in the method of derivative evaluation”

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- ▶ Sequential solution
 - ▶ You might have to solve an auxiliary problem for each guess

Multi-dimensional optimizers - If you must

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3. **Derivative-Free Nonlinear-Least-Squares (DFNLS):** Potentially very good
 - ▶ I don't know much about these
 - ▶ Use BOVYQA algorithm - Powell-like algorithm without derivatives

Global Optimizers

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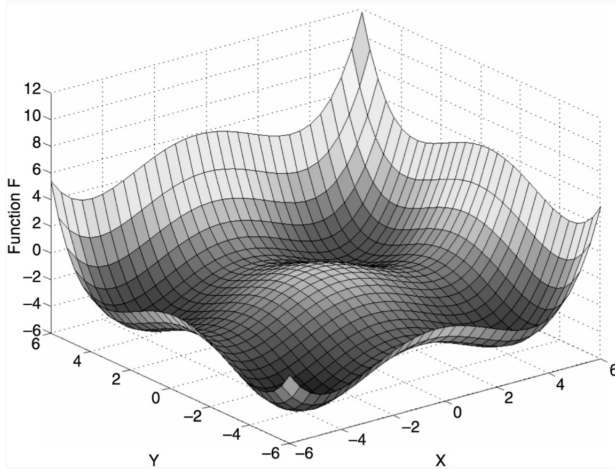
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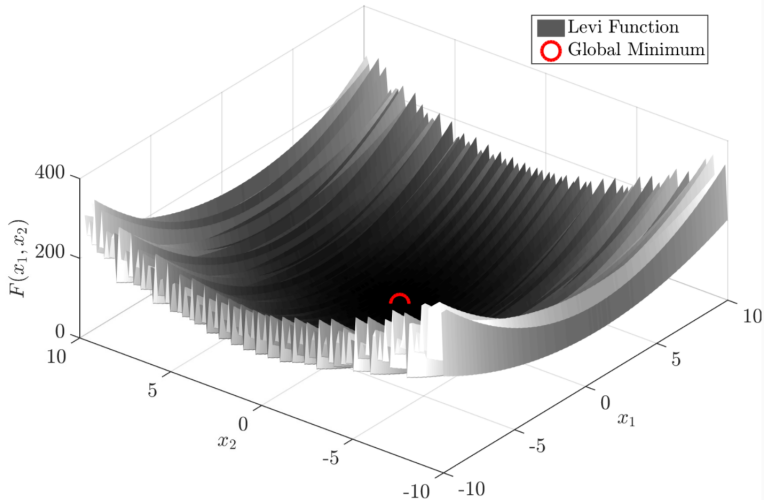
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- ▶ Nice alternative: TikTak algorithm, see Arnaud, Guvenen & Kleineberg (2020)

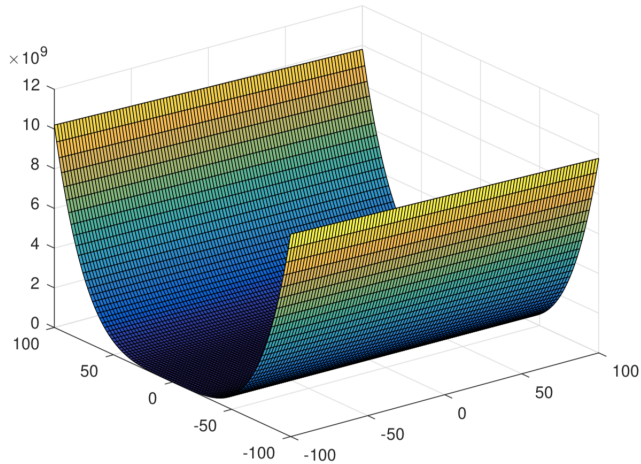
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- ▶ Use various starting points for your optimization routine (costly)

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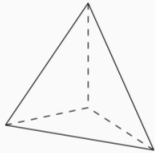
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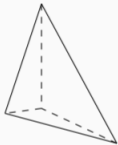
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- ▶ Three ways to do it: reflections, expansions and contractions
 - ▶ Reflections change one vertex and send it in the direction of the lowest evaluation
 - ▶ Expansions and contractions can be in a given direction or in all directions
- ▶ Easy to restart from a potential minimum

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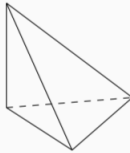
Initial Simplex



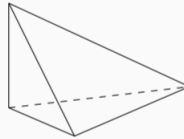
Contraction



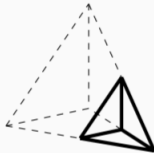
Reflection



Reflection and expansion



Contraction in all directions



TikTak

Algorithm 1: TikTak Global Optimizer

input : Number of seeds (N_0) and number of candidates (N^*)

output: Global optimum of function F

1. Generate a sequence of N_0 quasi-random **Sobol numbers** ;

2. Evaluate the function in N_0 points. Keep the best N^*

$$x_1, x_2, \dots, x_{N^*} \quad \text{s.t.} \quad F(x_1) \leq F(x_2) \leq \dots \leq F(x_{N^*}) ;$$

3. Set $x^* = x_1$ and $y^* = F(x_1)$;

for $i=1:N^*$ **do**

4.1. Let $\tilde{x}_0 = (1 - \theta_i)x_i + \theta_i x^*$ with $\theta_i \in [0, \bar{\theta}]$ is increasing in i , $\bar{\theta} < 1$;

4.2. Get local optimum: $\tilde{x} = \text{Optim}(F, \tilde{x}_0)$;

4.3. Update: $y^* = \max\{y^*, F(\tilde{x})\}$ and x^* ;

5. Return best result $(x^*, F(x^*))$

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Options:

1. Make a (Hyper-)Cartesian grid
 - ▶ Costliest solution of all, and still leaves too much space empty

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 - ▶ Costliest solution of all, and still leaves too much space empty
2. Draw random numbers from some distribution (usually uniform)
 - ▶ Sounds better... but in practice has bad “space coverage”
 - ▶ Capricious behavior (where points end up located)

Random vs Quasi-Random Numbers

- ▶ We often have to evaluate functions “covering the space”
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3. Quasi-random numbers: Deterministic sequences of numbers
 - ▶ Designed to spread maximally on a space
 - ▶ Build iteratively (next point in sequence fills out a portion of the space with less point density)

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Note: same idea as in Gauss-Kronrod quadrature integration

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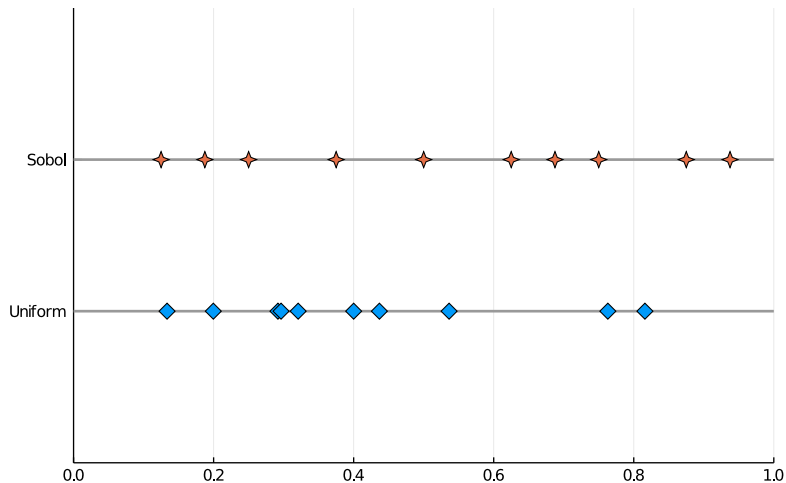
- ▶ Computing integrals by the Monte-Carlo method
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- ▶ Quasi-Monte Carlo integration uses quasi-random numbers
 - ▶ Increases convergence of integral
- ▶ Sobol numbers are particularly good

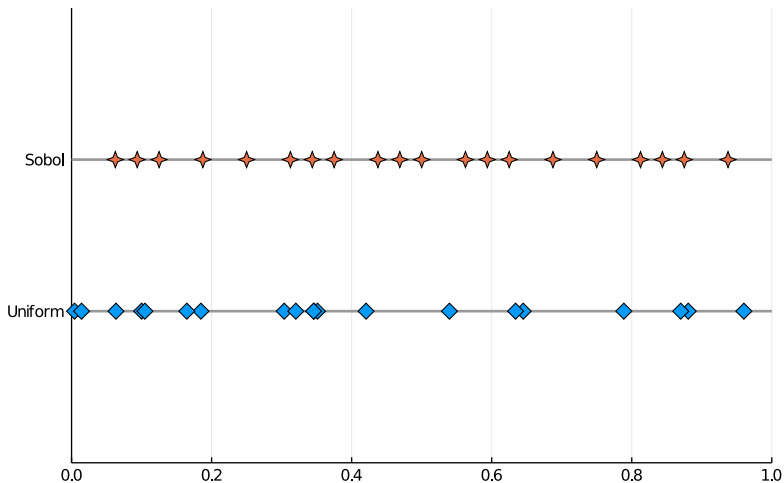
Sobol vs Uniform (1D)

Grid Points - $n=10$



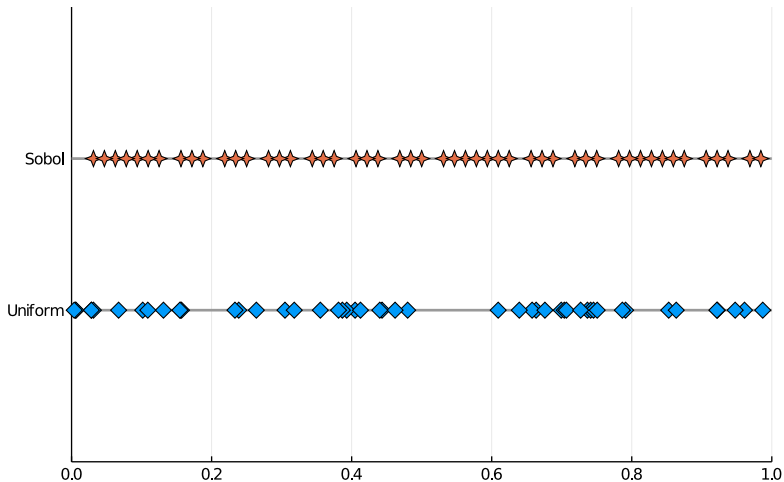
Sobol vs Uniform (1D)

Grid Points - $n=20$

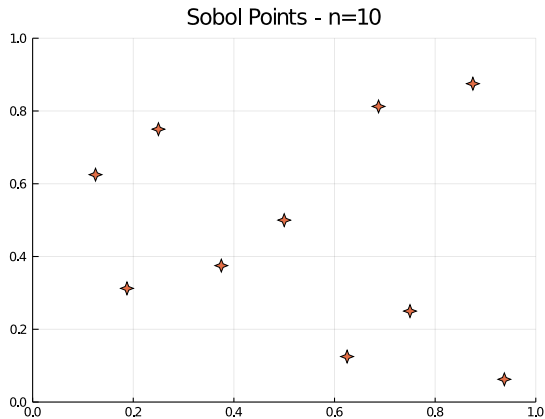
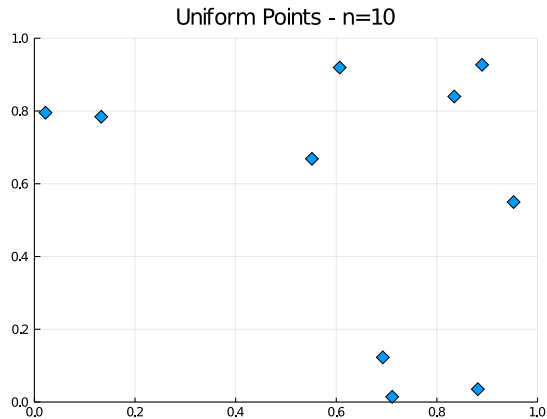


Sobol vs Uniform (1D)

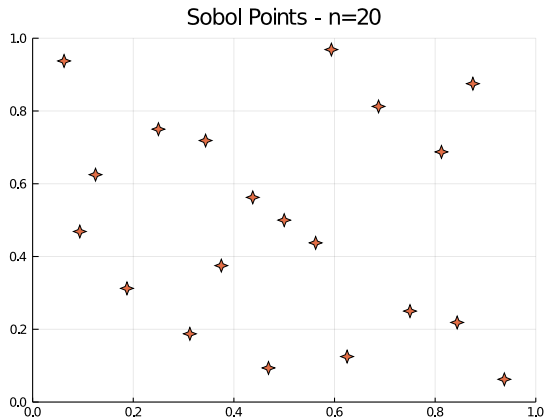
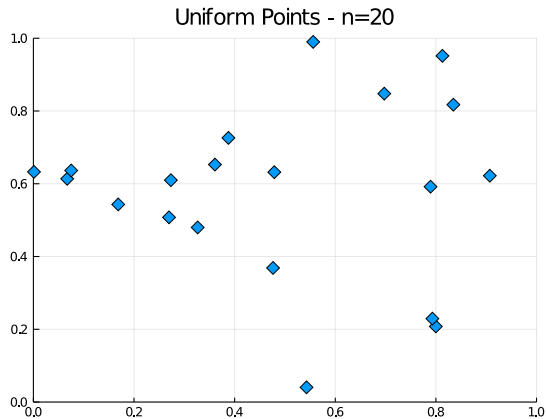
Grid Points - $n=50$



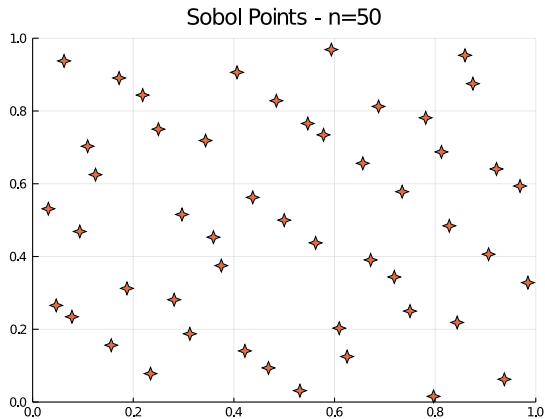
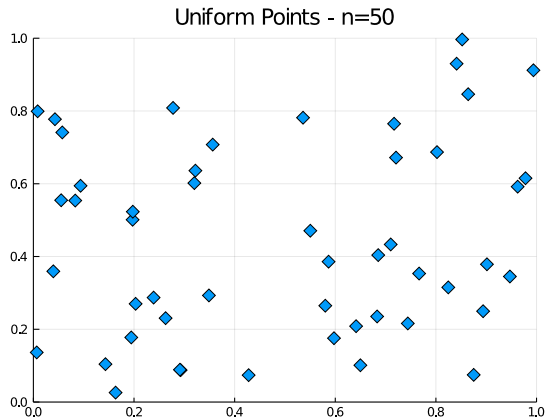
Sobol vs Uniform (2D) - Covering all the space



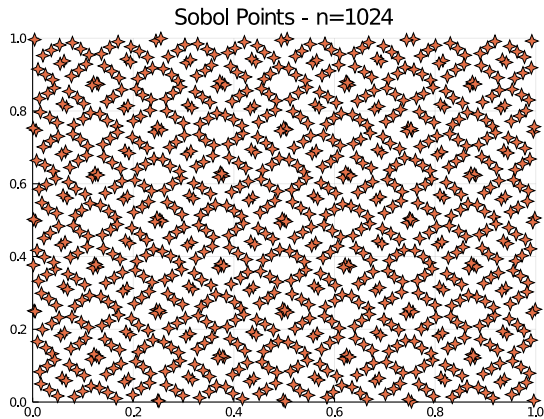
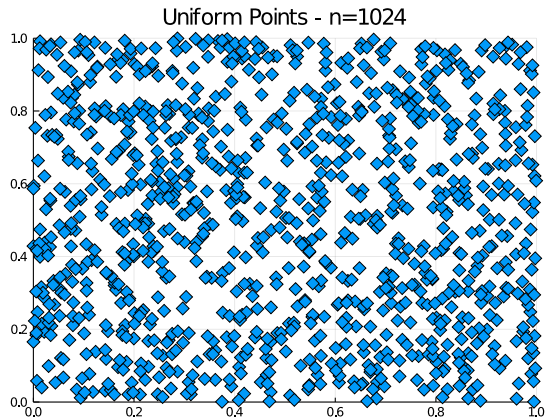
Sobol vs Uniform (2D) - Covering all the space



Sobol vs Uniform (2D) - Covering all the space



Sobol vs Uniform (2D) - Covering all the space



VFI with Continuous Optimization

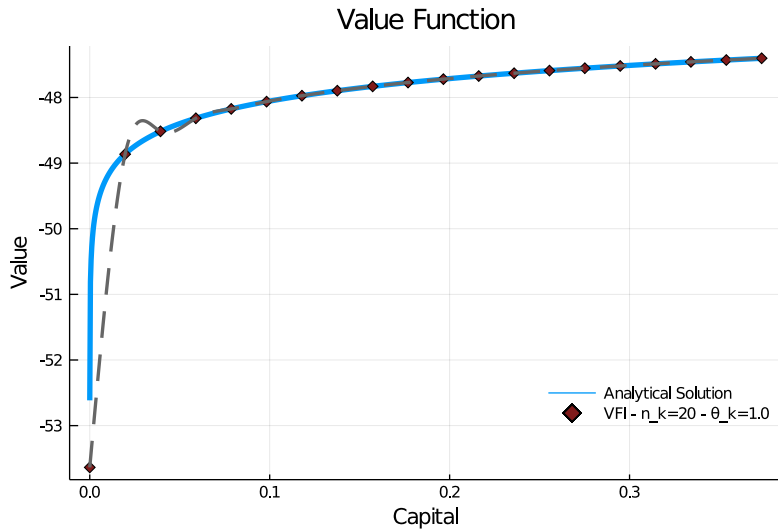
VFI - Algorithm

Algorithm 2: Bellman Operator: Continuous choice

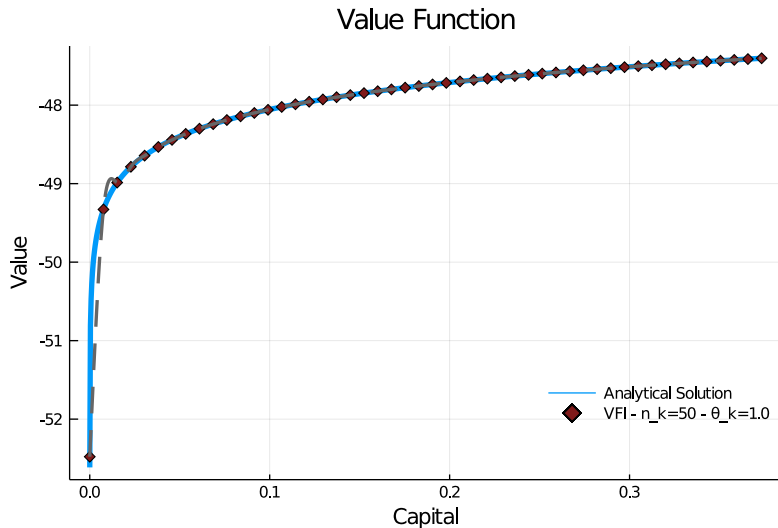
Function $T(V_old, k_grid, n_k, parameters)$:

```
for  $i = 1:n\_k$  do
    # Define objective function
     $F(k_p) = -U(k\_grid[i], k_p) - \beta * V_p(k_p)$ 
     $V_p(k_p) = \text{Interpolation}(k\_grid, V\_old, k_p)$ 
    # Find feasible range of  $k_p$ 
     $k\_min = 0$ ;  $k\_max = z * k\_grid[i]^\alpha - c\_min$ 
    # Check for corner solutions with derivative at bounds
     $k_p = k\_min$  if  $-dF(k\_min) < 0$ ;  $k_p = k\_max$  if  $-dF(k\_max) > 0$ ;
    # Solve min (Optional: Further bracket min before minimizing)
     $G\_kp[i] = \text{Optimize}(F, k\_min, k\_max)$ ;  $V\_new[i] = -F(k_p)$ 
return  $V\_new, G\_kp$ 
```

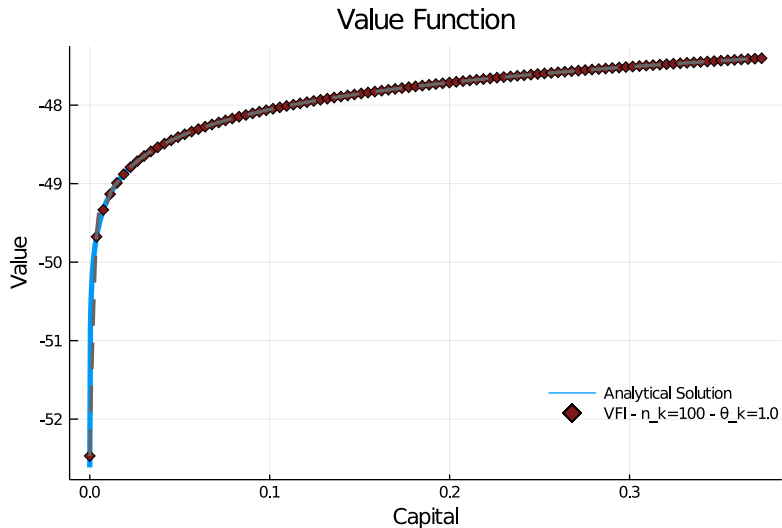
Value functions ($n_k = 20, 50, 100$)



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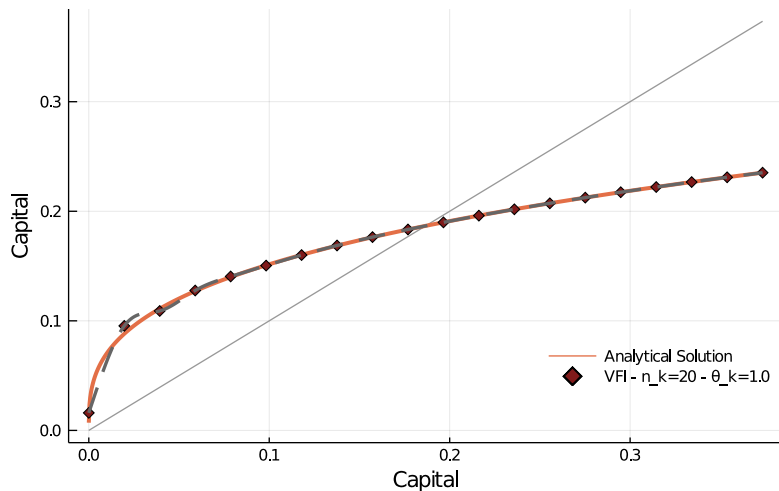


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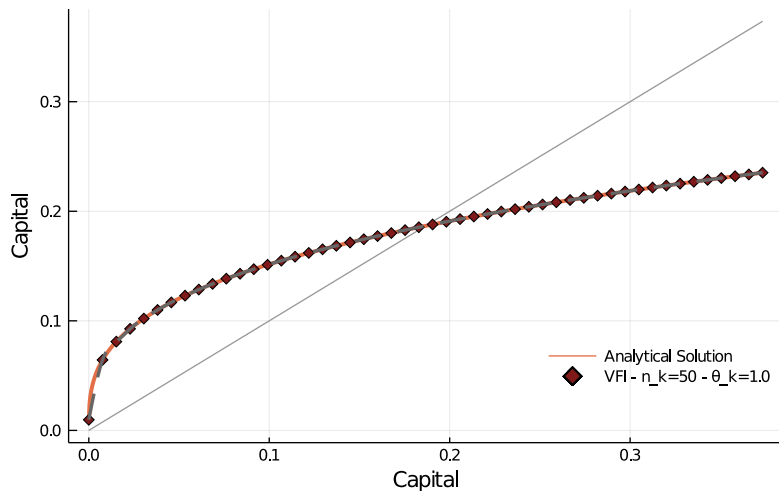
Policy functions ($n_k = 20, 50, 100$)

Policy Function - K



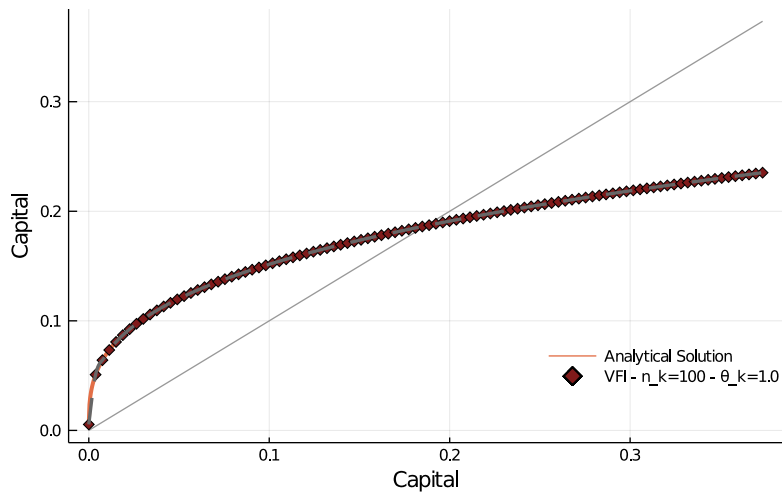
Policy functions ($n_k = 20, 50, 100$)

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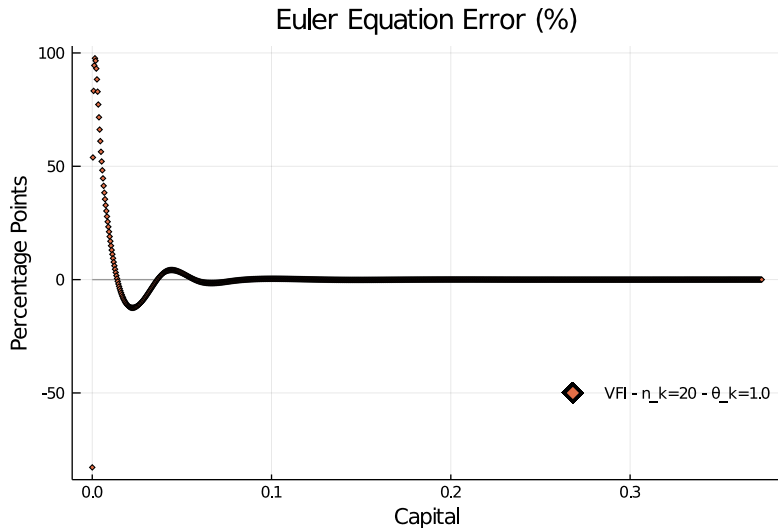


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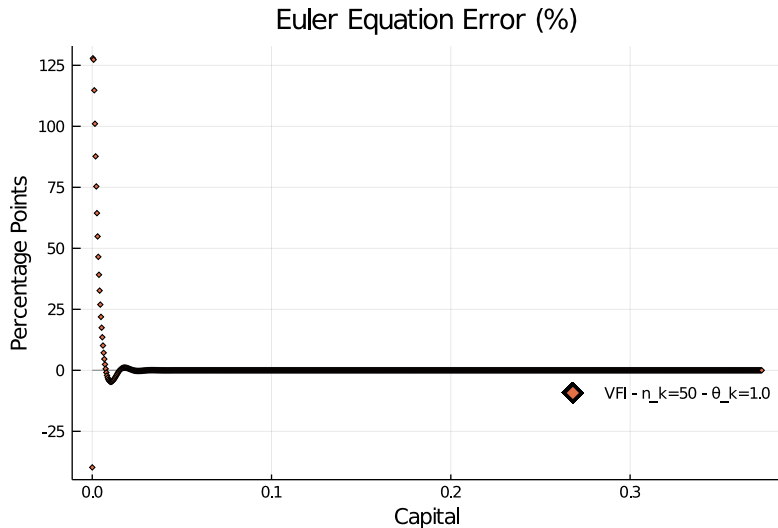
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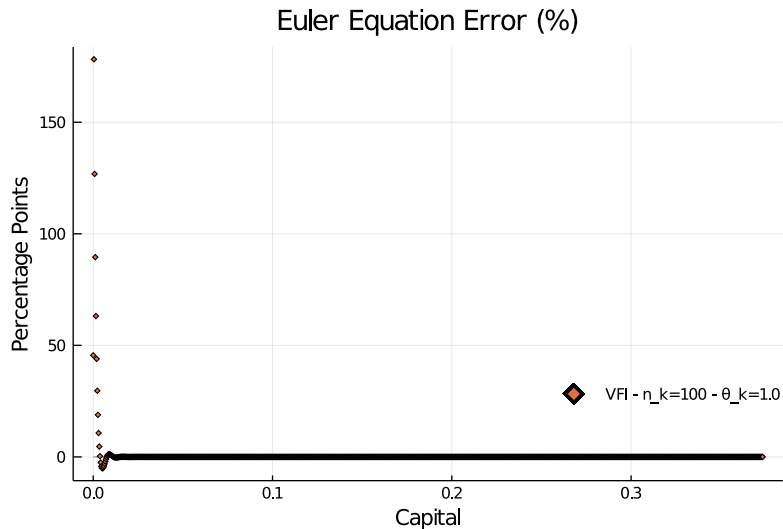
Euler Equation - Problems at the bottom



Euler Equation - Problems at the bottom

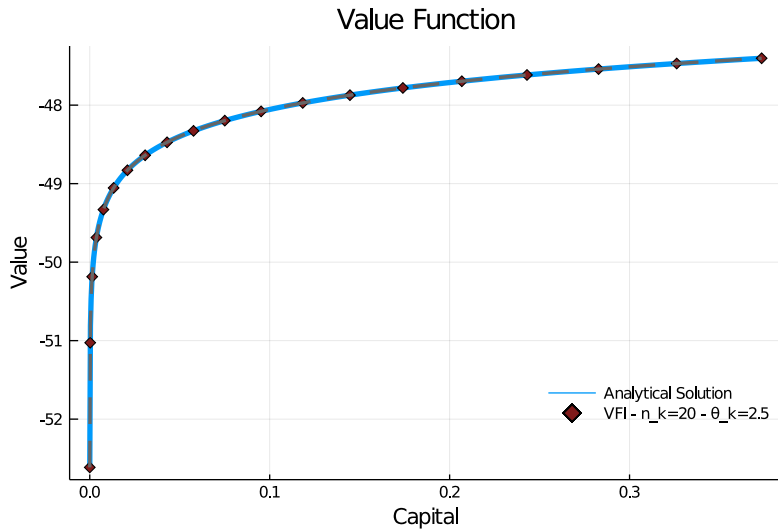


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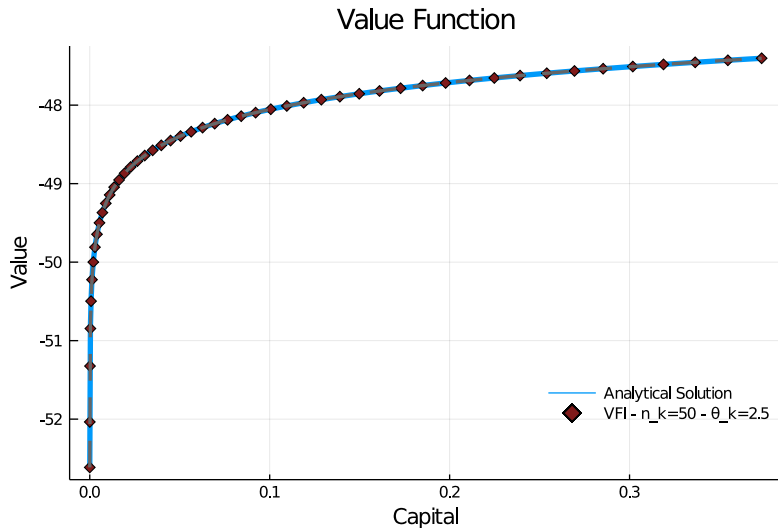


Revisiting Grid Spacing

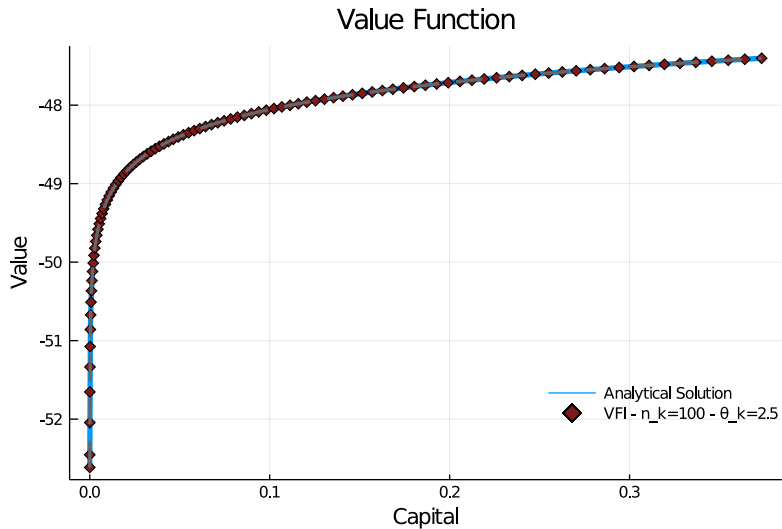
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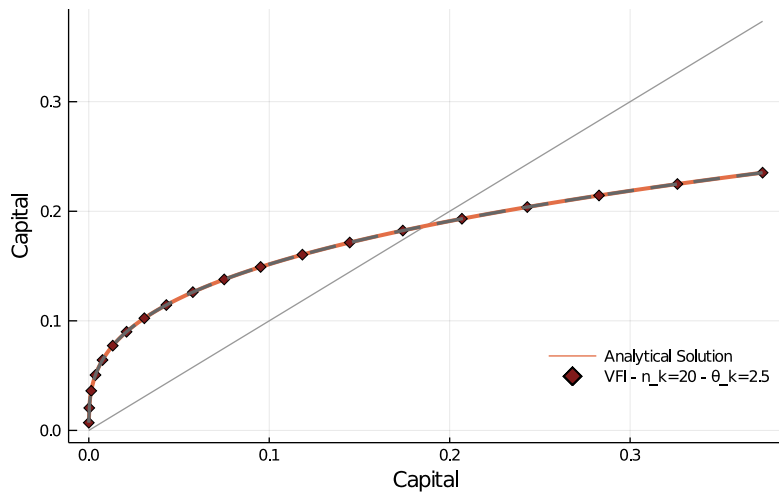


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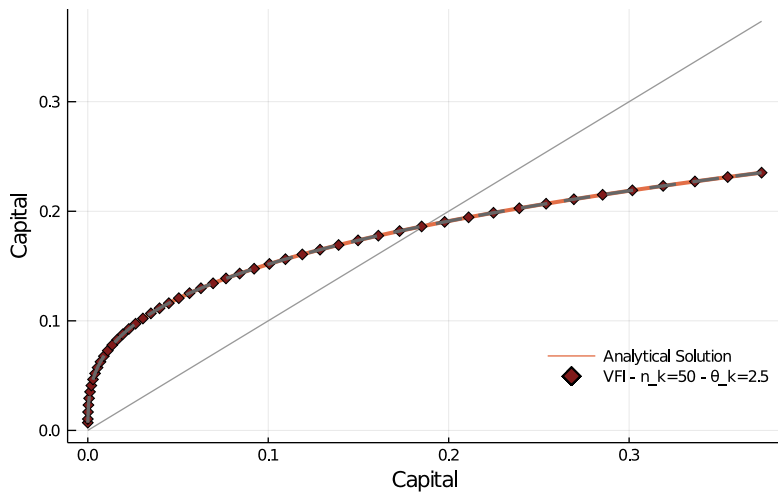
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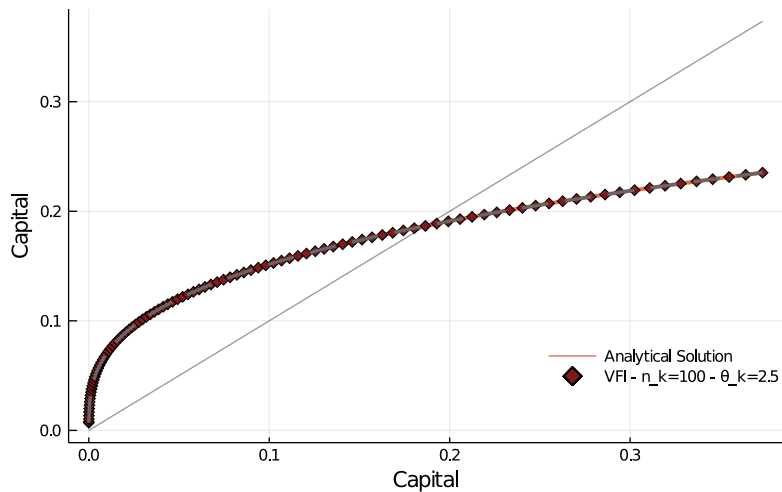
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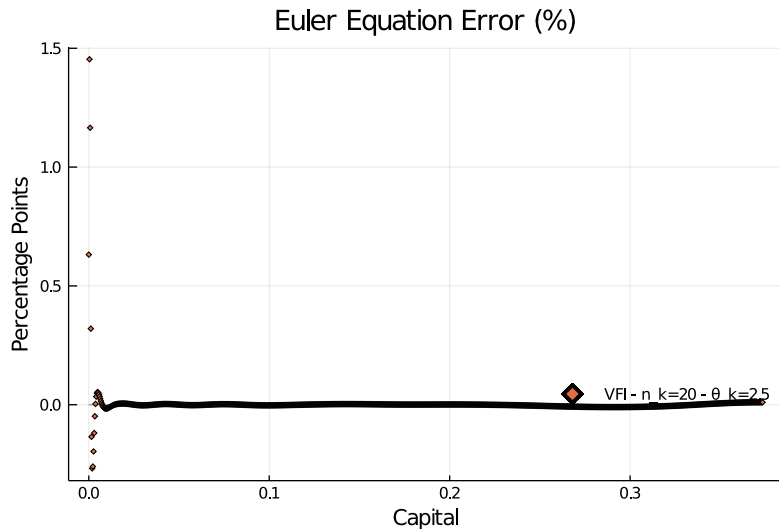


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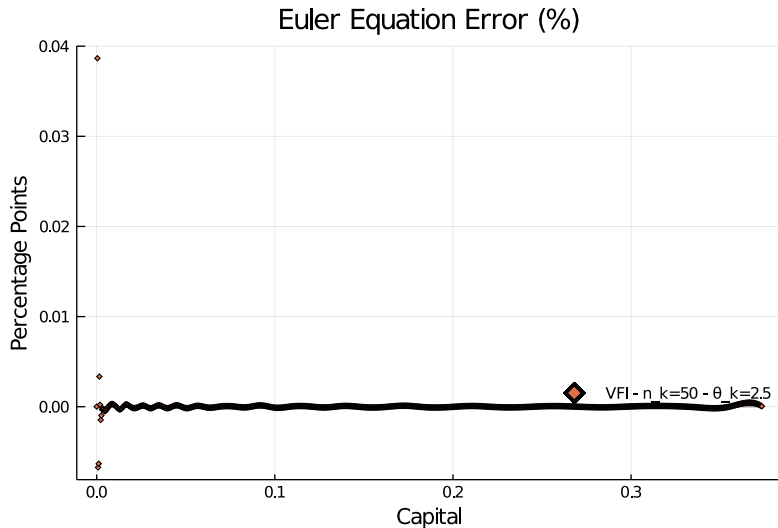
Policy Function - K



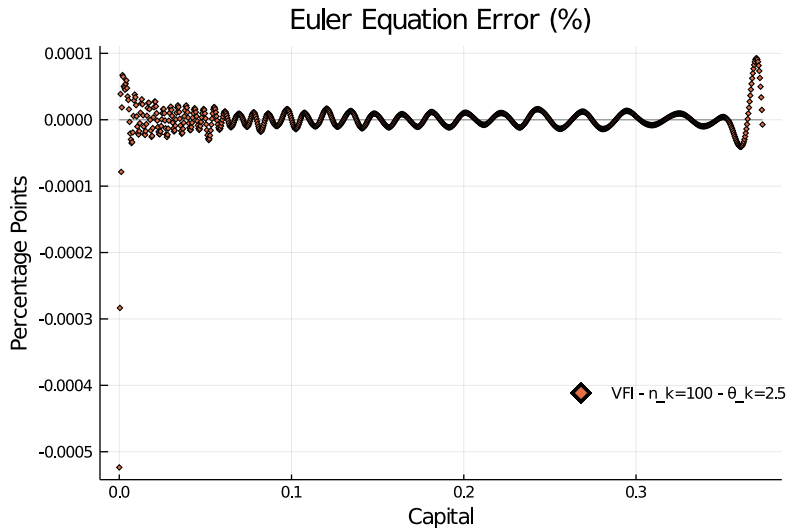
Euler Equation - No issues at the bottom



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Root Finding

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- ▶ Everything is very similar to what we have discussed
- ▶ Instead of maximizing the objective function we solve FOC
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 - ▶ Find root of Euler equation
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 - ▶ Minimize square of residual
- ▶ Root finding is particularly useful to find equilibrium prices
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- ▶ There are many other methods... depends on what you are doing

VFI - Algorithm

Algorithm 3: Bellman Operator: Continuous choice - Root finding

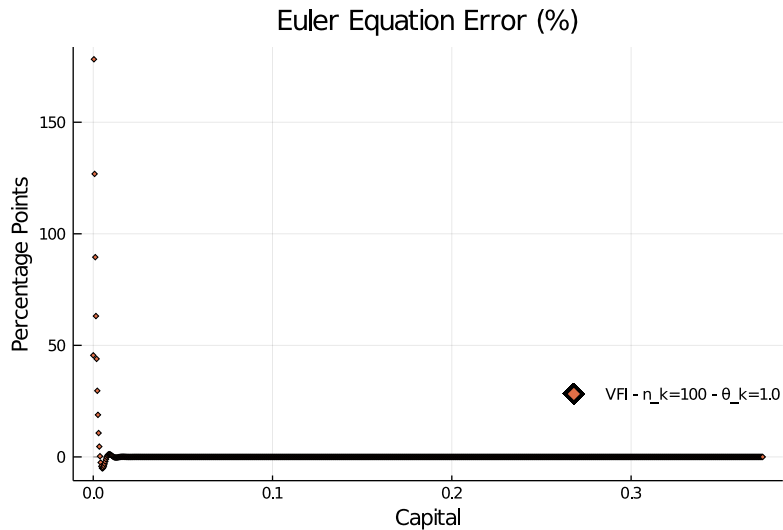
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```

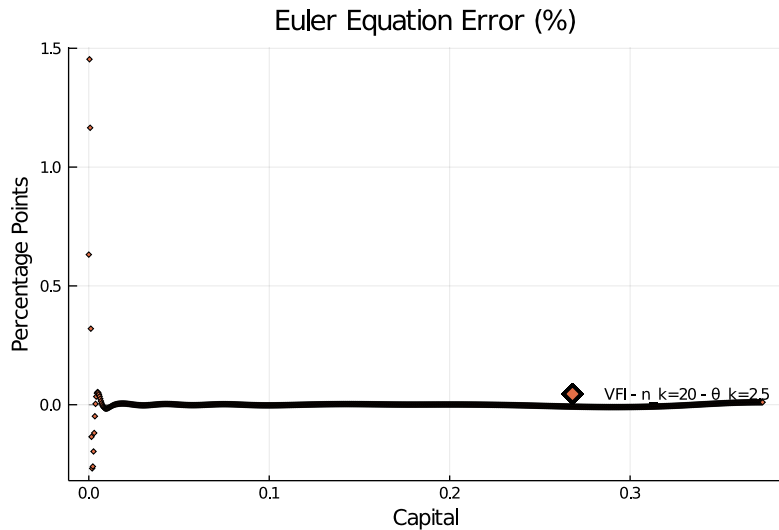
Euler Error ($n_k = 20, 50, 100$)

No Convergence for $n_k = 20, 50$ due to bad approximation to first derivative

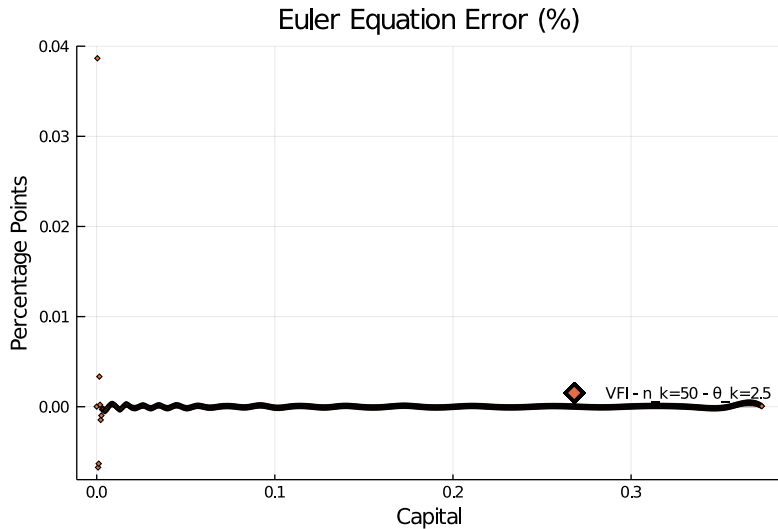
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Euler Equation - Curved Grid



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