

1 EQUILIBRIUM SYSTEM

Preferences:

$$E_0 \sum_{t=0}^{\infty} \beta^t [\log(c_t) - \chi n_t^{1+\eta} / (1 + \eta)]$$

Budget Constraint:

$$c_t + b_t / (i_t s_t) = w_t n_t + b_{t-1} / \pi_t + d_t$$

1.1 ART MODEL Equilibrium system (11 equations):

$$c_t = [1 - \varphi(\pi_t^{gap} - 1)^2 / 2] y_t \quad (1)$$

$$i_t^* = (i_{t-1}^*)^{\rho_i} (\bar{i}(\pi_t^{gap})^{\phi_\pi})^{1-\rho_i} \exp(\sigma_\nu \nu_t) \quad (2)$$

$$i_t = \max\{1, i_t^*\} \quad (3)$$

$$\lambda_t = c_t \quad (4)$$

$$w_t = \chi n_t^\eta \lambda_t \quad (5)$$

$$1 = \beta E_t[(\lambda_t / \lambda_{t+1})(s_t i_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (6)$$

$$\varphi(\pi_t^{gap} - 1) \pi_t^{gap} = 1 - \theta + \theta w_t / z_t + \beta \varphi E_t[(\lambda_t / \lambda_{t+1})(\pi_{t+1}^{gap} - 1) \pi_{t+1}^{gap} (y_{t+1} / y_t)] \quad (7)$$

$$y_t = z_t n_t \quad (8)$$

$$g_t = (1 - \rho_g) \bar{g} + \rho_g g_{t-1} + \sigma_\varepsilon \varepsilon_t \quad (9)$$

$$s_t = (1 - \rho_s) \bar{s} + \rho_s s_{t-1} + \sigma_v v_t \quad (10)$$

$$z_t = g_t z_{t-1} \quad (11)$$

Variables: $\{c, i^*, i, \lambda, w, \pi^{gap}, y, n, g, s, z\}$

De-trended Equilibrium System (10 equations):

$$\tilde{c}_t = [1 - \varphi(\pi_t^{gap} - 1)^2 / 2] \tilde{y}_t \quad (1)$$

$$i_t^* = (i_{t-1}^*)^{\rho_i} (\bar{i}(\pi_t^{gap})^{\phi_\pi})^{1-\rho_i} \exp(\sigma_\nu \nu_t) \quad (2)$$

$$i_t = \max\{1, i_t^*\} \quad (3)$$

$$\tilde{\lambda}_t = \tilde{c}_t \quad (4)$$

$$\tilde{w}_t = \chi n_t^\eta \tilde{\lambda}_t \quad (5)$$

$$1 = \beta E_t[(\tilde{\lambda}_t / \tilde{\lambda}_{t+1})(s_t i_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (6)$$

$$\varphi(\pi_t^{gap} - 1) \pi_t^{gap} = 1 - \theta + \theta \tilde{w}_t + \beta \varphi E_t[(\tilde{\lambda}_t / \tilde{\lambda}_{t+1})(\pi_{t+1}^{gap} - 1) \pi_{t+1}^{gap} (\tilde{y}_{t+1} / \tilde{y}_t)] \quad (7)$$

$$\tilde{y}_t = n_t \quad (8)$$

$$g_t = (1 - \rho_g) \bar{g} + \rho_g g_{t-1} + \sigma_\varepsilon \varepsilon_t \quad (9)$$

$$s_t = (1 - \rho_s) \bar{s} + \rho_s s_{t-1} + \sigma_v v_t \quad (10)$$

Variables: $\{\tilde{c}, i^*, i, \tilde{\lambda}, \tilde{w}, \pi^{gap}, \tilde{y}, n, g, s\}$

Log-linear Equilibrium System:

$$\hat{c}_t = \hat{y}_t \quad (1)$$

$$\hat{i}_t^n = \rho_i \hat{i}_{t-1}^n + (1 - \rho_i) \phi_\pi \hat{\pi}_t + \sigma_\nu \nu_t \quad (2)$$

$$\hat{i}_t = \hat{i}_t^n \quad (3)$$

$$\hat{\lambda}_t = \hat{c}_t \quad (4)$$

$$\hat{w}_t = \eta \hat{n}_t + \hat{\lambda}_t \quad (5)$$

$$\hat{\lambda}_t + \hat{i}_t + s_t = E_t \hat{\lambda}_{t+1} + E_t \hat{\pi}_{t+1} \quad (6)$$

$$\varphi \hat{\pi}_t = (\theta - 1) \hat{w}_t + \beta \varphi E_t \hat{\pi}_{t+1} \quad (7)$$

$$\hat{y}_t = \hat{n}_t \quad (8)$$

1.2 GUST ET AL MODEL Equilibrium system (13 equations):

$$\varphi(\pi_t^{gap} - 1)\pi_t^{gap} = V_{\pi,t} \quad (1)$$

$$i_t^* = (i_{t-1}^*)^{\rho_i} (\bar{i}(\pi_t^{gap})^{\phi_\pi})^{1-\rho_i} \exp(\sigma_\nu \nu_t) \quad (2)$$

$$i_t = \max\{1, i_t^*\} \quad (3)$$

$$1/\lambda_t = V_{\lambda,t} \quad (4)$$

$$\lambda_t = c_t \quad (5)$$

$$c_t = [1 - \varphi(\pi_t^{gap} - 1)^2/2]y_t \quad (6)$$

$$w_t = \chi n_t^\eta \lambda_t \quad (7)$$

$$V_{\lambda,t} = \beta E_t[(1/\lambda_{t+1})(s_t i_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (8)$$

$$V_{\pi,t} = 1 - \theta + \theta w_t / z_t + \beta \varphi E_t[(\lambda_t / \lambda_{t+1})(\pi_{t+1}^{gap} - 1)\pi_{t+1}^{gap}(y_{t+1}/y_t)] \quad (9)$$

$$y_t = z_t n_t \quad (10)$$

$$g_t = (1 - \rho_g)\bar{g} + \rho_g g_{t-1} + \sigma_\varepsilon \varepsilon_t \quad (11)$$

$$s_t = (1 - \rho_s)\bar{s} + \rho_s s_{t-1} + \sigma_v \nu_t \quad (12)$$

$$z_t = g_t z_{t-1} \quad (13)$$

Variables: $\{c, i^*, i, \lambda, w, \pi^{gap}, V_\lambda, y, V_\pi, n, g, s, z\}$

De-trended Equilibrium System (12 equations):

$$\varphi(\pi_t^{gap} - 1)\pi_t^{gap} = \tilde{V}_{\pi,t} \quad (1)$$

$$i_t^* = (i_{t-1}^*)^{\rho_i} (\bar{i}(\pi_t^{gap})^{\phi_\pi})^{1-\rho_i} \exp(\sigma_\nu \nu_t) \quad (2)$$

$$i_t = \max\{1, i_t^*\} \quad (3)$$

$$1/\tilde{\lambda}_t = \tilde{V}_{\lambda,t} \quad (4)$$

$$\tilde{\lambda}_t = \tilde{c}_t \quad (5)$$

$$\tilde{c}_t = [1 - \varphi(\pi_t^{gap} - 1)^2/2]\tilde{y}_t \quad (6)$$

$$\tilde{w}_t = \chi n_t^\eta \tilde{\lambda}_t \quad (7)$$

$$\tilde{V}_{\lambda,t} = \beta E_t[(1/\tilde{\lambda}_{t+1})(s_t i_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (8)$$

$$\tilde{V}_{\pi,t} = 1 - \theta + \theta \tilde{w}_t + \beta \varphi E_t[(\tilde{\lambda}_t / \tilde{\lambda}_{t+1})(\pi_{t+1}^{gap} - 1)\pi_{t+1}^{gap}(\tilde{y}_{t+1}/\tilde{y}_t)] \quad (9)$$

$$\tilde{y}_t = n_t \quad (10)$$

$$g_t = (1 - \rho_g)\bar{g} + \rho_g g_{t-1} + \sigma_\varepsilon \varepsilon_t \quad (11)$$

$$s_t = (1 - \rho_s)s_t + \rho_s s_{t-1} + \sigma_v \nu_t \quad (12)$$

Variables: $\{\tilde{c}, i^*, i, \tilde{\lambda}, \tilde{w}, \pi^{gap}, \tilde{V}_\lambda, \tilde{y}, \tilde{V}_\pi, n, g, s\}$

Log-linear Equilibrium System:

$$\varphi \hat{\pi}_t = \hat{V}_{\pi,t} \quad (1)$$

$$\hat{i}_t^n = \rho_i \hat{i}_{t-1}^n + (1 - \rho_i) \phi_\pi \hat{\pi}_t + \sigma_\nu \nu_t \quad (2)$$

$$\hat{i}_t = \hat{i}_t^n \quad (3)$$

$$-\hat{\lambda}_t = \hat{V}_{\lambda,t} \quad (4)$$

$$\hat{\lambda}_t = \hat{c}_t \quad (5)$$

$$\hat{c}_t = \hat{y}_t \quad (6)$$

$$\hat{w}_t = \eta \hat{n}_t + \hat{\lambda}_t \quad (7)$$

$$\hat{V}_{\lambda,t} = \hat{i}_t + s_t - E_t \hat{\lambda}_{t+1} - E_t \hat{\pi}_{t+1} \quad (8)$$

$$\hat{V}_{\pi,t} = (\theta - 1) \hat{w}_t + \beta \varphi E_t \hat{\pi}_{t+1} \quad (9)$$

$$\hat{y}_t = \hat{n}_t \quad (10)$$

Gust et al Indicator Functions

$$\tilde{V}_{\lambda,t,1} = \beta E_t [(1/\tilde{\lambda}_{t+1})(s_t \hat{i}_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (1)$$

$$\tilde{V}_{\lambda,t,2} = \beta E_t [(1/\tilde{\lambda}_{t+1})(s_t / (\bar{\pi} \pi_{t+1}^{gap} g_{t+1}))] \quad (2)$$

for $k = 1, 2$ where $k = 1$ corresponds to the non-ZLB regime and $k = 2$ corresponds to the ZLB regime.

$$V_{l,t} = V_{l,t,1} I + V_{l,t,2} (1 - I) \quad (3)$$

for $l \in \{\lambda\}$ and $j = 1, 2$ and where I is defined by:

$$\begin{cases} I = 1 & \text{if } i > 1 \\ I = 0 & \text{otherwise.} \end{cases}$$