

# Robust investments under risk and ambiguity

Harold Zurcher's robust replacement policy

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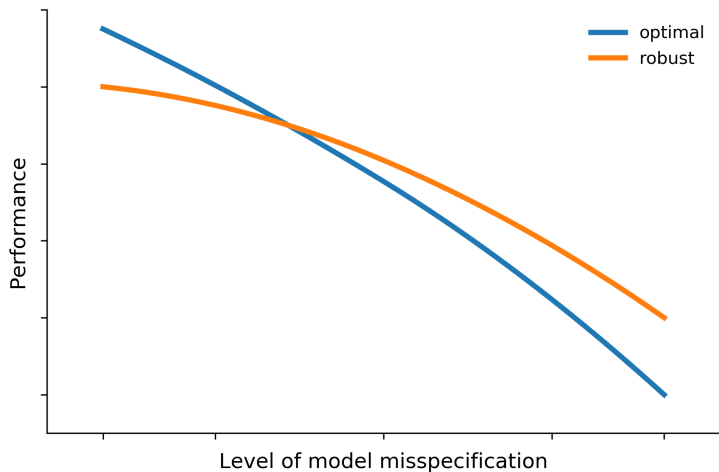
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# Introduction

# Introduction

- Policy makers vote for climate change mitigation efforts facing uncertainty about future costs and benefits (Barnett, Brock, & Hansen, 2020).
- Investors trade with assets uncertain about future returns (Epstein & Schneider, 2008).
- Young adults decide on their careers in light of uncertainty about future job outcomes (Keane & Wolpin, 1997).

# Notion of Robust decision rule



# Questions addressed in our research

- How sensitive is the performance of the optimal decision rule?
- When does a robust decision rule perform better?
- How to construct a robust decision rule?

## Decision making under risk: Revisiting Rust (1987)

## A brief summary



General State

Mileage/Age

New Engine (\$\$\$)

Maintenance (\$-\$)





# The framework

- Single agent Markov decision problem over infinite horizon.
- The agent decides each month  $t$  to maintain  $i_t = 0$  or replace  $i_t = 1$  the bus engine.
- Mileage  $x_t$  is discretized in states of length 5000 miles.
- If the engine is replaced,  $x_t$  is set to 0.

# Optimal decision

The optimal decision in each period  $t$  can be inferred from the Bellman equation (Bellman (1954)):

$$V_{\theta}(x_t) = \max_{i_t \in \{0,1\}} \left[ u(x_t, i_t, \theta_1) + \epsilon_t(i_t) + \beta EV_{\theta}(x_t, i_t) \right]$$

with

$$u(x_t, i_t, \theta_1) = \begin{cases} -c(x_t, \theta_1) & \text{if } i_t = 0 \\ -RC & \text{if } i_t = 1 \end{cases}$$

and unobserved utility shock  $\epsilon_t(i_t)$ .

# Estimation strategy

Rust (1987) assumes Conditional Independence (CI):

$$p(x_{t+1}, \epsilon_{t+1} | x_t, \epsilon_t, i_t, \theta_2, \theta_3) = q(\epsilon_{t+1} | \theta_2) p(x_{t+1} | x_t, i_t, \theta_3)$$

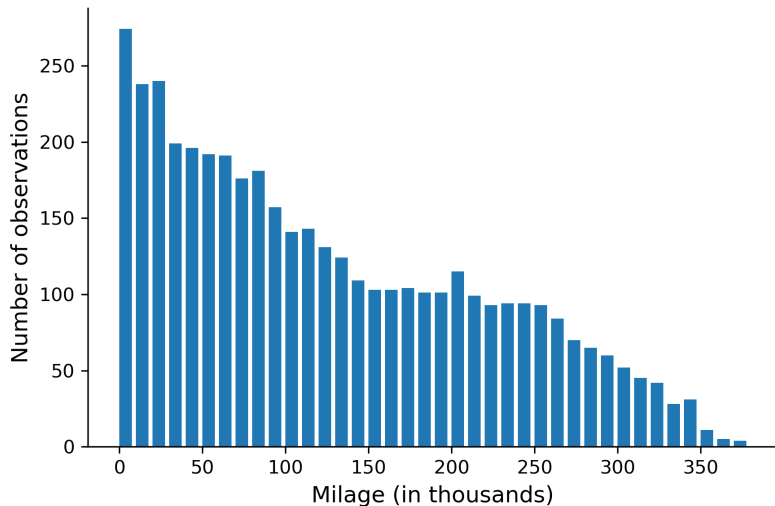
This allows to estimate the model in two steps:

$$\max_{\theta_3} \prod_{t=1}^T p(x_t | x_{t-1}, i_{t-1}, \theta_3)$$

Second:

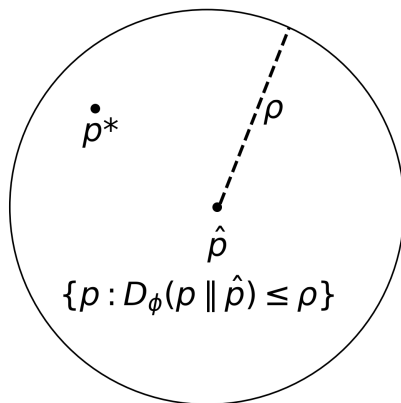
$$\max_{RC, \theta_1} \prod_{t=1}^T P(i_t | x_t, \theta)$$

# Differences in estimation quality



## Assessing the ambiguity

# Constructing the ambiguity set

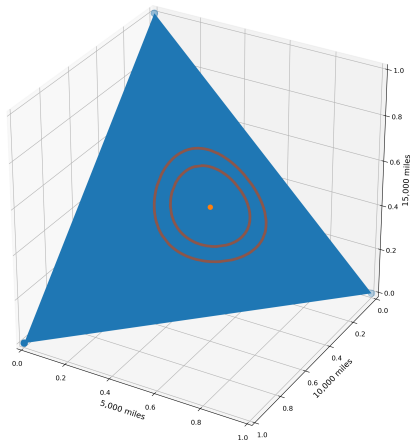


# Calibrating the ambiguity set

Following Ben-Tal et al. (2013), we can calibrate the size of the ambiguity set with the number of observations  $N_x$  for state  $x \in X$ :

$$\begin{aligned}
 \omega &= \mathbb{P}\{p_x^* \in \mathcal{P}_x\} \\
 &= \mathbb{P}\{p_x^* \in \{p : D(p||\hat{p}_x) \leq \rho_x\}\} \\
 &\approx \mathbb{P}\{\chi^2_{|X|-1} \leq 2N_x\rho_x\} \\
 &= F_{|X|-1}(2N_x\rho_x) \\
 \Rightarrow \rho_x &= F_{|X|-1}^{-1}(\omega)/2N_x
 \end{aligned}$$

# Probability simplex





## Decision making under risk and ambiguity

# Theory

Ben-Tal, El Ghaoui, and Nemirowski (2009) develop, building on Wald (1950), the following idea of robust decision making:

- Robust decision making can be modeled as a game agent vs. nature.
- First the agent chooses his action to maximize his present value.
- Then nature chooses the transition probabilities accordingly to minimize the agent's value.
- As the agent and nature have common information, the agent chooses in the first step the alternative with the highest (max) minimal (min) value.

# Rectangularity

The set of all transition probabilities associated with decision rule  $d$ :

$$\mathcal{F}^d = \{\mathbf{p} : \forall x \in X, p(x) \in \mathcal{P}_x^{d(x)}\}.$$

We assume that the set of probability distributions on the set of all possible histories  $\mathcal{H}$  is rectangular:

$$\left\{ \mathbf{P} : \forall h \in \mathcal{H}, \mathbf{P}(h) = \prod_{t=0}^{\infty} p(x_t), p(x_t) \in \mathcal{F}^d, t = 0, 1, \dots \right\} = \prod_{t=0}^{\infty} \mathcal{F}^d$$

$\Rightarrow$  **nature's choices are uncoupled over time and states.**

# Theory

Rectangularity allows to carry over the results of the classic dynamic programming problem. The robust Bellman equation in the model setup of Rust (1987):

$$V_{\theta}(x_t) = \max_{i_t \in \{0,1\}} \left[ u(x_t, i_t, \theta_1) + \epsilon_t(i_t) + \beta \min_{p_x \in \mathcal{P}_x^{i_t}} EV_{\theta}(x_t, i_t) \right]$$

In comparison, the standard Bellman equation from before:

$$V_{\theta}(x_t) = \max_{i_t \in \{0,1\}} \left[ u(x_t, i_t, \theta_1) + \epsilon_t(i_t) + \beta EV_{\theta}(x_t, i_t) \right]$$

# Application

# Setup and structure

## Setup:

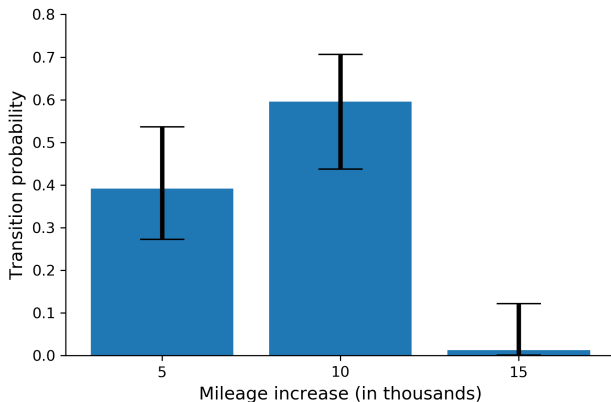
- Original transition probabilities, but mimicked state specific estimation.
- Increased cost of maintenance and engine replacement.

## Structure of analysis:

- Transition probabilities
- Policy features
- Policy performance

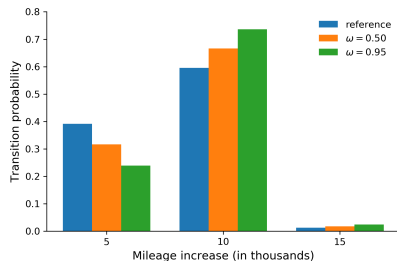
## Transition probabilities

# Estimated transition probabilities

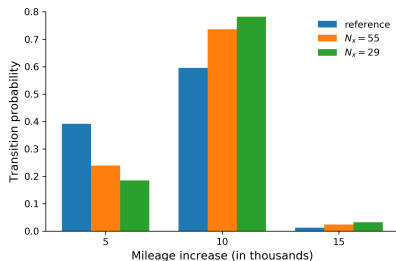




# Worst case distribution



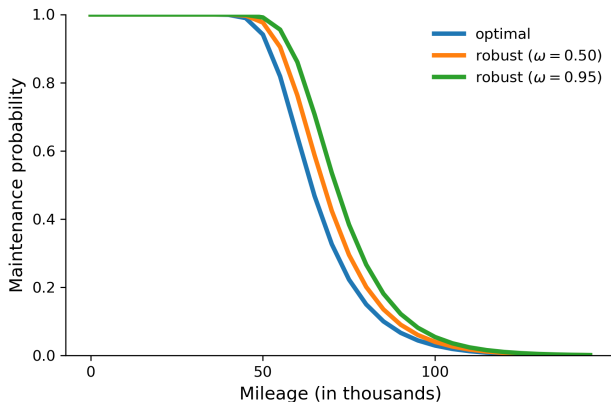
Variation in  $\omega$ , ( $N_x = 55$ )



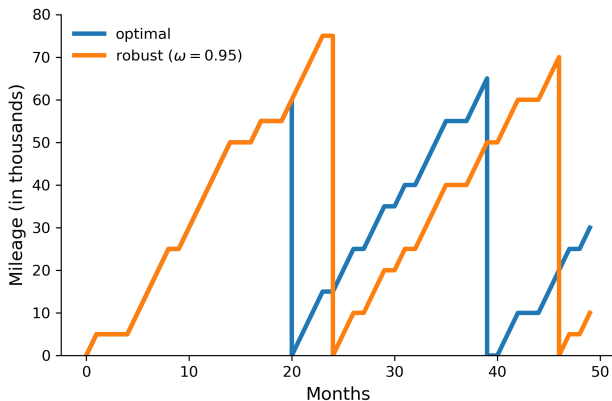
Variation in  $N_x$ , ( $\omega = 0.95$ )

## Policy features

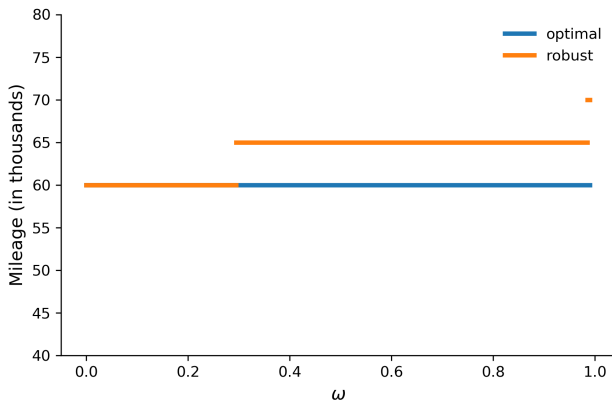
# Shift in maintenance probabilities



# Simulation setup

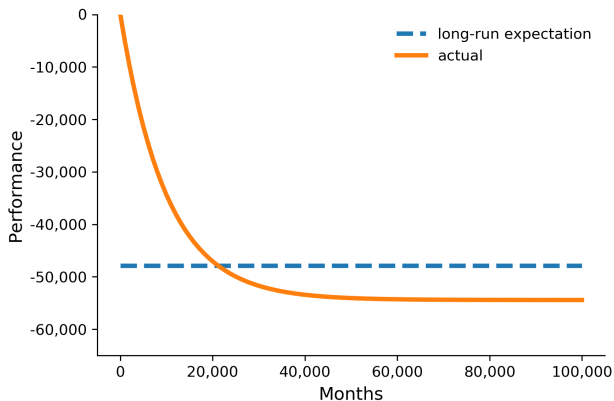


# Mean mileage at replacement

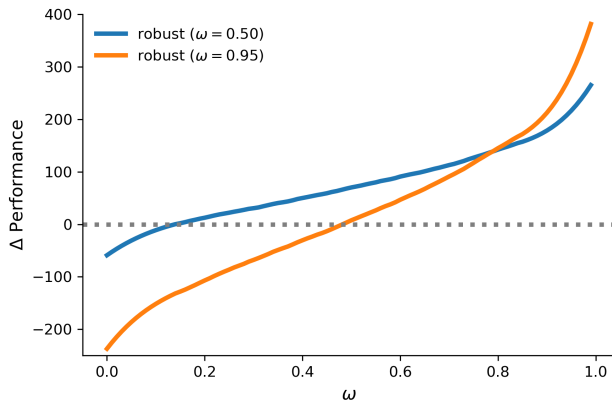


# Policy performance

# Performance of optimal policy

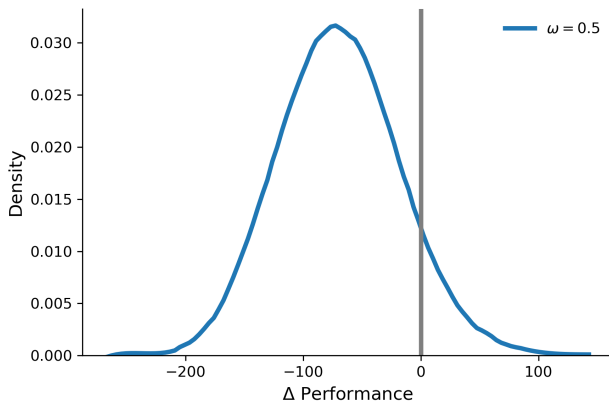


# Performance on the boundary

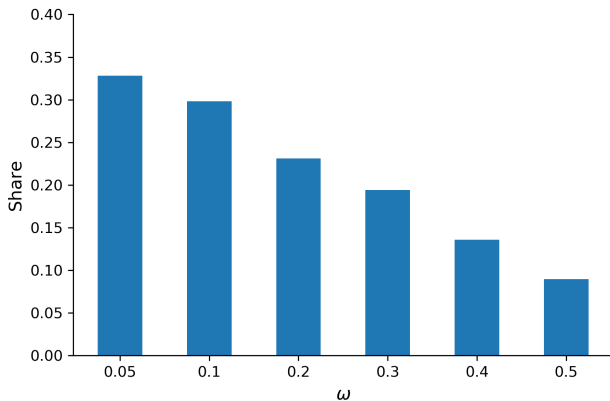




# Validation



# Validation



## Conclusion

# Thank you for your attention

## References I

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