Matching DSGE models, VARs, and state space models

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Outline

- Alternative representations of the solution of a DSGE model.
- Fundamentalness and finite VAR representation of DSGE solutions.
- Linking DSGE and VARs with sign restrictions.
- Some empirical concerns.
- Dealing with non-fundamentalness

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1 Solution of DSGE models

• Typical (Log-) linearized solution of a DSGE model is of the form:

$$y_{2t} = A_{22}(\theta)y_{2t-1} + A_{21}(\theta)y_{3t}$$
(1)

$$y_{1t} = A_{11}(\theta)y_{2t-1} + A_{12}(\theta)y_{3t}$$
(2)

 y_{2t} = states (endogenous and exogenous), y_{1t} = controls, y_{3t} shocks.

- $\mathcal{A}_{ij}(\theta), i, j = 1, 2$ are time invariant (reduced form) matrices and depend on θ , the structural parameters of technologies, policies, etc.

- There are cross equation restrictions since $\theta_i, i = 1, \ldots, n$ appears in more than one entry of these matrices.

- (1)-(2) is a state space model, with (1) being the transition equation and (2) the measurement equation.

- If both y_{2t} and y_{1t} are observables (1)-(2) is also a restricted VAR(1).

- Restrictions are on the lag length and on the entries of the coefficient matrix.

Letting
$$W_t = [y_{2t}, y_{1t}]', u_t = y_{3t}$$

$$\mathcal{A}_0 = \begin{bmatrix} A_{21} & 0 \\ 0 & A_{12} \end{bmatrix}^{-1}, \quad \mathcal{A}(\ell) = \begin{bmatrix} A_{21} & 0 \\ 0 & A_{12} \end{bmatrix}^{-1} \begin{bmatrix} A_{22} & 0 \\ A_{11} & 0 \end{bmatrix}$$

Then the system is

$$W_t = \mathcal{A}(\ell)W_{t-1} + u_t \tag{3}$$

- Singular system: dim $(y_{3t}) < dim(y_{1t} + y_{2t})$.

2 Alternative representations for y_{1t}

1) If \mathcal{A}_{12} is invertible

$$y_{3t} = \mathcal{A}_{12}^{-1}(y_{1t} - \mathcal{A}_{11}y_{2t-1})$$

 $y_{2t} = \mathcal{A}_{22}y_{2t-1} + \mathcal{A}_{21}\mathcal{A}_{12}^{-1}(y_{1t} - \mathcal{A}_{11}y_{2t-1})$
 $(1 - (\mathcal{A}_{22} - \mathcal{A}_{21}\mathcal{A}_{12}^{-1}\mathcal{A}_{11})\ell)y_{2t} = \mathcal{A}_{21}\mathcal{A}_{12}^{-1}y_{1t}$

If $\mathcal{A}_{22} - \mathcal{A}_{21} \mathcal{A}_{12}^{-1} \mathcal{A}_{11}$ has all eigenvalues less than 1

$$y_{2t} = (1 - (\mathcal{A}_{22} - \mathcal{A}_{21}\mathcal{A}_{12}^{-1}\mathcal{A}_{11})\ell)^{-1}\mathcal{A}_{21}\mathcal{A}_{12}^{-1}y_{1t}$$

 and

$$y_{1t} = \mathcal{A}_{11}(1 - (\mathcal{A}_{22} - \mathcal{A}_{21}\mathcal{A}_{12}^{-1}\mathcal{A}_{11})L)^{-1}\mathcal{A}_{21}\mathcal{A}_{12}^{-1}y_{1t-1} + \mathcal{A}_{12}y_{3t}$$
(4)

- If only y_{1t} is observable, the solution solution is a VAR (∞) .

- Does it make sense to assume that A_{12} is invertible? We need to have as many controls as shocks. Typically, this condition is not satisfied. Add measurement error to make this condition work.

- Need invertibility conditions on the eigenvalues of $A_{22} - A_{21}A_{12}^{-1}A_{11}$.

2) If A_{11} is invertible

$$y_{2t-1} = \mathcal{A}_{11}^{-1}(y_{1t} - \mathcal{A}_{12}y_{3t})$$
$$\mathcal{A}_{11}^{-1}(y_{1t+1} - \mathcal{A}_{12}y_{3t+1}) = \mathcal{A}_{22}\mathcal{A}_{11}^{-1}(y_{1t} - \mathcal{A}_{12}y_{3t}) + \mathcal{A}_{21}y_{3t}$$
$$y_{1t+1} = \mathcal{A}_{11}\mathcal{A}_{22}\mathcal{A}_{11}^{-1}y_{1t} + (\mathcal{A}_{11}\mathcal{A}_{21} - \mathcal{A}_{11}\mathcal{A}_{22}\mathcal{A}_{11}^{-1}\mathcal{A}_{12})y_{3t} + \mathcal{A}_{12}y_{3t+1})$$
$$y_{1t+1} = \mathcal{A}_{11}\mathcal{A}_{22}\mathcal{A}_{11}^{-1}y_{1t} + (I + (\mathcal{A}_{11}\mathcal{A}_{21}\mathcal{A}_{12}^{-1} - \mathcal{A}_{11}\mathcal{A}_{22}\mathcal{A}_{11}^{-1})\ell)y_{4t+1}$$

where $y_{4t} \equiv A_{12}y_{3t}$.

- If only y_{1t} is observable solution is a VARMA(1,1)

- Does it make sense to assume that \mathcal{A}_{11} is invertible? Need as many controls as states.

- No need to impose restrictions on the eigenvalues of $A_{22} - A_{21}A_{12}^{-1}A_{11}$.

3) Final form computations
From 2)
$$y_{1t} = \mu_1 y_{1t-1} + u_t + \nu_1 u_{t-1}$$
. Then for any $\begin{pmatrix} y_{1t}^1, y_{1t}^2 \end{pmatrix}$
 $\begin{bmatrix} 1 - \mu_{11}\ell & -\mu_{12}\ell \\ -\mu_{21}\ell & 1 - \mu_{22}\ell \end{bmatrix} \begin{bmatrix} y_{1t}^1 \\ y_{1t}^2 \end{bmatrix} = \begin{bmatrix} 1 - \nu_{11}\ell & \nu_{12}\ell \\ \nu_{21}\ell & 1 + \nu_{22}\ell \end{bmatrix} \begin{bmatrix} u_t^1 \\ u_t^2 \end{bmatrix}$

Note that
$$det(\nu(\ell)) = (1 + \nu_{11}\ell)(1 + \nu_{22}ell) - \nu_{12}\nu_{21}\ell^2$$
. Then:

$$\begin{bmatrix} 1 + \nu_{22}\ell & -\nu_{21}\ell \\ -\nu_{12}\ell & 1 + \nu_{11}\ell \end{bmatrix} \begin{bmatrix} 1 - \mu_{11}\ell & -\mu_{12}\ell \\ -\mu_{21}\ell & 1 - \mu_{22}\ell \end{bmatrix} \begin{bmatrix} y_{2t}^1 \\ y_{2t}^2 \end{bmatrix} = det(\nu(\ell)) \begin{bmatrix} u_t^1 \\ u_t^2 \end{bmatrix}$$

Under this alternative representation, the solution for y_{1t} is a VARMA(2,2).

• If $\nu(\ell)$ is of reduced rank, write $\nu(\ell) = \begin{bmatrix} 1 + \nu_{11}\ell & \alpha\nu_{11}\ell \\ \nu_{21}\ell & 1 + \alpha\nu_{21}\ell \end{bmatrix}$ some α . Then $det(\nu(\ell)) = 1 + (\nu_{11} + \nu_{21})\ell$.

In this case the solution for y_{1t} is a VARMA(2,1).

2.1 An important digression

The above representations assume that the state y_{2t} is observable. What if it is not?

- Typically, one needs to compute Kalman filter forecast of it, i.e. $\hat{y}_{2t} = (A_{22} - KA_{11})\hat{y}_{2t-1} + K\hat{y}_{1t}$ where K is the Kalman gain which depends on the observables y_{1t} .

- Adding and subtracting $A_{11}\hat{y}_{2t}$ to (2) we have

$$y_{1t} = A_{11}\hat{y}_{2t-1} + u_t \tag{5}$$

$$u_t = A_{11}(y_{2t-1} - \hat{y}_{2t-1}) + A_{12}y_{3t}$$
(6)

• If the states are not observables and the observable y_{1t} fail to perfectly reveal them, i.e. $y_{2t-1} \neq \hat{y}_{2t-1}$, the innovations of the model include not only the structural shocks but also the forecast errors make in predicting the non-observable states.

Why is this relevant? If, for example, news shocks are present, they will be state variables, but they are not observable. Thus an econometrician needs to forecast them using the observables.

- The condition that the eigenvalues of $(A_{22} - A_{21}A_{12}^{-1}A_{11})$ are all less than one in modulus implies that $\Sigma_u = A_{12}\Sigma_{y_3}A'_{12}$ and that the forecast errors disappear

- This condition is equivalent to saying that with the observables variables we can perfectly reconstruct the unobservable states.

Example 1 Suppose that the capital stock is a state and it is unobservable. Then the effect of capital as a state can be recovered from a VAR if he variables included allow to perfectly predict it. Thus, for example, VARs without investment will not satisfy the condition on the eigenvalues of $(A_{22} - A_{21}A_{12}^{-1}A_{11})$

• Think about the potential structural model which has generated the data before choosing the variables of a VAR!

When the eigenvalue condition is not satisfied the covariance matrix of the VAR innovations is strictly larger than the covariance matrix of the structural innovations.

• $A_{11}\Sigma_{y_2}A'_{11}$ could be small if y_{1t} reveals well the information about y_{2t} . Thus it is possible to find models which are non-invertible and still VARs approximately well their dynamics. **Example 2** Sims (2011) consider a standard medium scale New Keynesian model of the type used in central banks. The model has a technology shock and a news shock which enter in the model via

$$\ln TFP_t = a + \ln TFP_{t-1} + e_t + v_{t-q}$$
(7)

where v_{t-q} is a a news shocks about the level of the technology known q periods in advance. This process has the following state space representation

$$\ln TFP_t = a + \ln TFP_{t-1} + e_t + z_{1,t-1}
 z_{1,t} = z_{2,t-1}
 z_{2,t} = z_{3,t-1}
 \vdots
 z_{q-1,t} = u_{t-q}$$
(8)

Thus, we have trasformed (7) into a vector of process with a "fake"" state vector z_t .

In the model, agents keep track of the z's when computing their optimal decisions. Econometricians do not know or observe the z's. Thus the state vector cannot, in general, be observed based on a history of observables TFP.

Given a standard parameterization and v = 4 periods of foresight, the maximum eigenvalues of the $(A_{22} - A_{21}A_{12}^{-1}A_{11})$ is 1.32. Thus the invertibility conditions fails. Nevertheless

the distortions that an econometrician would generate estimating a VAR on the data simulated by the model would be small (see below). Here we assume that the identification of the shocks is corrrect.



The solid lines are the theoretical impulse responses to news and surprise technology shocks in the "Full Model" using the parameterization as described in the text. For the Monte Carlo exercises the VARs feature $\ln \hat{a}_t$ and $\ln \hat{y}_t$ and are estimated with p = 8 lags. In the left panel, labeled "Finite Sample," the dashed lines are the mean responses averaged across 500 simulations of data sets with 200 observations each, while the shaded gray regions depict the middle 68 percent of the distribution of estimated responses across the 500 simulations. In the right panel, labeled "Large Sample," the dashed lines are the estimated impulse responses from the estimation on one sample with 100,000 observations.

Conclusions

- If variables are omitted, the solution of the model has a VAR representation only in certain (restricted) conditions.

- Even if a VAR representation exists, it may not allow us to recover the true shocks, if observables do not the information about missing states.

- Invertibility is not a either or propositions. There are non-invertible systems which could be recovered well with VARs.

- Can we use a finite VAR to approximate a DSGE model? If the eigenvalue condition holds, generally yes.

3 An alternative setup

Here we use the specification:

$$y_t = Px_{t-1} + Qz_t \tag{9}$$

$$x_t = Rx_{t-1} + Sz_t \tag{10}$$

$$Z(\ell)z_t = \epsilon_t \tag{11}$$

where y_t is $r \times 1$, z_t is $m \times 1$, x_t is $n \times 1$. The difference with the previous setup is that here endogenous and exogenous states are differentiated.

We want to solve out the z_t in both cases below. In addition, in one case x_t is observable, in the other it is not.

Case 1). Suppose both
$$x_t$$
 and y_t are observable. Let $Y_t = [x_t, y_t]$, $A = \begin{bmatrix} R & 0 \\ P & 0 \end{bmatrix}$, $B = \begin{bmatrix} S \\ Q \end{bmatrix}$ and let $Z(\ell) = I - z_1 \ell$. Then

$$Y_t = AY_{t-1} + Bz_t \qquad (12)$$

$$z_t = z_1 z_{t-1} + \epsilon_t \qquad (13)$$

This is an ARMA(1,1) representation (it is used for example in Kommunjer and Ng (2011)).

Letting B^G be the generalized inverse of B,we have

$$z_{t} = B^{G}(Y_{t} - AY_{t-1}) \equiv z_{1}(B^{G}Y_{t-1} - B^{G}AY_{t-2}) + \epsilon_{t}$$
(14)

Thus

$$Y_{t} = AY_{t-1} + B[z_{1}B^{G}Y_{t-1} - Bz_{1}B^{G}AY_{t-2}] + B\epsilon_{t}$$

= $(A + Bz_{1}B^{G})Y_{t-1} - B^{2}z_{1}B^{G}AY_{t-2} + B\epsilon_{t}$ (15)

Note: Y_t is $n + r \times 1$ while ϵ_t is $m \times 1$.

- If
$$m = n + r$$
, $B^G = B^{-1}$ and $Y_t = (A + z_1)Y_{t-1} - Bz_1AY_{t-2} + B\epsilon_t$.

• If B is invertible, the representation is a VAR(2).

- If m < n + r, $B^G \neq B^{-1}$ system driven by a small number of shocks relative to the observables.

• If B admits a generalized inverse, the representation is still a VAR(2)! This means that we can delete rows and using any combinations of element \hat{Y}_t of Y_t we can make a non-singular VAR(2).

- There will be problems using maximum likelihood to estimate the parameters since covariance matrix is singular. If we want to use it need to drop endogenous variables until m = n + r. Which ones to drop? How do you do this? (see Canova, Ferroni and Matthes, 2012). Case 2). Suppose that only y_t are observables and assume m = r.

Results:

1) \hat{Y}_t is a VARMA(n+pm,n+p(m-1)), where p is the number of lags in the representation of z_t .

2) A finite order VAR representation for \hat{Y}_t exists iff either det[$|I - R\ell| + Padj(I - R\ell)SQ^{-1}\ell$] is of degree zero in ℓ or det[$|I - (RSQ^{-1}P)\ell$] is of degree zero in ℓ .

3) 2) holds also if $Y_t = [x_t, y_t]$ where x_t is $n_1 < n \times 1$ and y_t is $r - n_1 \times 1$.

Implications

1) Eliminating endogenous states from the VAR leads to a much more complicated VARMA representation. The length of the AR and MA depend on the size of the x_t and y_t vectors, the assumed process for the exogenous states. In general, a VAR must have very long lags to approximate the solution.

2) Need a particular configuration of parameters to generate a finite order VAR representation. Need restrictions on P, R, Q, S matrices.

3) A necessary and sufficient condition for the existence of a finite order VAR is that the determinant of $(I - (RSQ^{-1}P)L]$ is of degree zero in L (compare with the eigenvalue restrictions we had before).

4) We need a particular setup where the number of observable (controls) y_t matches exactly the number of exogenous shocks.

• Conditions appear to be restrictive in general.

4 VAR misspecification and sign restrictions

- Consider the first setup.

- If use robust sign restriction are used to identify shocks, misrepresentation (with a finite order VAR) of the decision rules less important.

DSGE models:

$$y_{2t} = \mathcal{A}_{22}(\theta)y_{2t-1} + \mathcal{A}_{21}(\theta)y_{3t}$$
(16)

$$y_{1t} = \mathcal{A}_{11}(\theta)y_{2t-1} + \mathcal{A}_{12}(\theta)y_{3t}$$
(17)

This model fits into the general VAR setup

$$\begin{bmatrix} I - F_{11}\ell & F_{12}\ell \\ F_{21}\ell & I - F_{22}\ell \end{bmatrix} \begin{bmatrix} y_{1t} \\ y_{2t} \end{bmatrix} = \begin{bmatrix} G_1 \\ G_2 \end{bmatrix} e_t$$

Representation for y_{1t} (integrating out y_{2t}):

$$(I - F_{11}\ell - F_{12}F_{21}(1 - F_{22}\ell)^{-1}\ell^2)y_{1t} = [G_1 - (F_{12}(1 - F_{22}\ell)^{-1}G_2\ell]e_t$$
(18)

- This is, in general, a ARMA (∞,∞) .
- Impact effects of e_t on y_{1t} has the correct sign and the right magnitude.

Still there could be problems:

- Shocks in the reduced system will be time aggregated.

- Representation is not one-sided (future values of the shocks enter the representation).

5 Practical implications for SVAR analyses.

Let $y_t = \sum_{j=0}^{\infty} a_j e_{t-j}$ be the reduced form MA representation of the observable data where $a_0 = I$, $e_t \sim (0, \Sigma)$ are the innovations in the process, that is, $e_t = y_t - P(y_t|I_{t-1})$ where I_{t-1} is the information set available at time t - 1.

Take the first representation of the (log-) linearized solution of a DSGE as your structural model. Solving the state equation we get

$$y_{2t} = \mathcal{A}_{21}(\theta) \sum_{j=0}^{\infty} \mathcal{A}_{22}(\theta)^j y_{3t-j}$$
 (19)

Plugging this equation in the equation for y_{1t} we have

$$y_{1t} = \mathcal{A}_{11}(\theta) \mathcal{A}_{21}(\theta) \sum_{j=1}^{\infty} \mathcal{A}_{22}(\theta)^{j} y_{3t-j} + \mathcal{A}_{12}(\theta) y_{3t}$$
(20)

Let $y_t = S[y_{2t}, y_{1t}]'$ where S is a selection matrix. Then

$$e_{t} = S[y_{2t}, y_{1t}]' - E_{t-1}S[y_{2t}, y_{1t}]'$$
(21)
$$= S[\mathcal{A}_{21}(\theta) \sum_{j=0}^{\infty} \mathcal{A}_{22}(\theta)^{j} y_{3t-j},$$

$$\mathcal{A}_{11}(\theta) \mathcal{A}_{21}(\theta) \sum_{j=1}^{\infty} \mathcal{A}_{22}(\theta)^{j} y_{3t-j} + \mathcal{A}_{12}(\theta) y_{3t}]'$$
(22)
$$- E_{t-1}S[\mathcal{A}_{21}(\theta) \sum_{j=0}^{\infty} \mathcal{A}_{22}(\theta)^{j} y_{3t-j},$$

$$\mathcal{A}_{11}(\theta) \mathcal{A}_{21}(\theta) \sum_{j=1}^{\infty} \mathcal{A}_{22}(\theta)^{j} y_{3t-j} + \mathcal{A}_{12}(\theta) y_{3t}]'$$
(23)

- If y_t is a vector with the same dimensions as y_{3t} and I_{t-1} includes y_{2t-1}

then

$$e_t = A_{12}y_{3t}$$
 (24)

and we are in the standard setup. If some or all y_{2t} are omitted $y_{2t} - E_{t-1}y_{2t}$ will produce a forecast error. Then

$$e_t = A_{12}y_{3t} + S[y_{2t} - E_{t-1}y_{2t}, \ \mathcal{A}_{11}(\theta)(y_{2t} - E_{t-1}y_{2t})]'$$
(25)

so that the structural errors will be contaminated by the forecast errors. Thus

1) e_t will not be a white noise. There could be autocorrelation and heteroschedasticity if the forecast errors are autocorrelated and heteroschedastic.

2) The size of the distortion due to omitted variables depends on the entries of $\mathcal{A}_{11}(\theta)$ and how distant is the info set I_{t-1} from y_{2t} ; that is, whether or not the variables in I_{t-1} help to forecast y_{2t} or not.

- 3) Structural innovations will be determined with error.
- The dynamic responses will not be necessarily wrong.
- Variance decomposition generally wrong.
- Counterfactuals generally wrong.

6 Potential problems: Permanent income

Here is a simple example of how inference could be wrong when some variables are non-obserables.

Assume the income process is $y_t = y_{t-1} + \sigma_w w_t$.

If utility depends on consumption and it is quadratic, the consumption Euler equation is

$$c_{t+1} = \beta c_t + \sigma_w (1 - R^{-1}) w_{t+1}$$
(26)

where β is the discount factor and R > 1 the constant interest rate. Suppose that c_t is non-observable and instead we observe $s_t = y_t - c_t$. The optimality condition for saving is:

$$s_{t+1} = -c_t + \sigma_w R^{-1} w_t$$
 (27)

The vector (c_t, s_t) forms a state space model. The process for s_t is non-fundamental (non-invertible) since $\beta + R - 1 > 1$ and this violate the eigenvalue condition. The fundamental representation for savings is

$$s_{t+1} = -\hat{c}_t + \sigma_w(\frac{\beta - 1 + R}{R})e_{t+1}$$
 (28)

where $\hat{c}_{t+1} = \beta \hat{c}_t + \sigma_w (\frac{\beta - \beta^2 + 1}{R} - \beta) e_{t+1}$ and e_t is the fundamental innovation (i.e. the forecast error made in forecasting s_{t+1} using current and past information).

To see what the two representations imply compute the ARMA(1,1) representations for saving in the model and in the fundamental representation:

$$s_{t+1} = \beta s_t + \sigma_w R^{-1} w_{t+1} - \sigma_w (1 - R^{-1} + \beta R^{-1}) w_t$$

$$s_{t+1} = \beta s_t + \sigma_w (\frac{\beta - 1 + R}{R}) e_{t+1} - \sigma_w R^{-1} e_t$$

Conclusions:

1) In the model the immediate effect is $\sigma_w R^{-1}$; in the fundamental representation it is $\sigma_w(\frac{\beta-1+R}{R})$ Since $\beta - 1 + R > 1$, the impact effect is overestimated.

2) By the same toke, the lagged effect is underestimated.

3) In the model the lagged effect is larger $1 - R^{-1} + \beta R^{-1} > R^{-1}$. In the fundamental model the opposite is true.

4) $e_t \neq w_t$. In particular w_t are linear combinations of current and future e'_t 's. Thus, using current and past values of s_t allows us to recover current values of e_t but not current values of w_t .

7 Dealing with non-invertibility problems

Not clear how to solve non-fundamental problems in practice. many alternatives have been suggested:

- Expand the observable vector (hoping to capture the effect of future shocks) (See e.g. Ramey (2011)). How do we know that this is enough?

- Use a factor model setup (see Forni and Gambetti (2010)). It can deal with non-fundamentalness due to omitted variables but it has not much to say about model based non-fundamentalness.

- Estimate directly the structural model (Fernandez et al. (2007)). Full information likelihood methods will have problems: likelihood has multiple peaks with non-invertibility. Dispense completely with VAR setup.

- Ravn and Mertens (2010). Use theory (calibrated DSGE) to tell us about the root that create non-fundamentalness. Fix it based on theory and proceed in VAR analysis from there.

- Dupor and Han (2011). Four step approach:

i) Estimate an ARMA(1,1) model from the data.

ii) Compute all possible covariance equivalent representation of the estimated model.

iii) Identify shocks and compute impulse responses for all possible representations.

iv) Eliminate representations which fail to satisfy additional restrictions (e.g. variance decomposition restrictions (size of variance explained), sign or shape restrictions, etc.).

Problem is step iv). Restrictions have to be determined by investigator. Potentially debatable.

True question is whether fundamental representation and one or more nonfundamental representations differ and in what way; if differences are small issue minor.

Procedure somewhat cumbersome for medium-large scale VAR.

Requires somewhat stringent assumptions about

- the number of observables and the number of shocks (they must be the same). Need to add measurement errors most of the time.

- the number of states and the number of controls must be the same. Need to have non-minimal state space representation.

Idea: Start from

$$\begin{aligned}
x_{t+1} &= Qx_t + Ue_{t+1} \\
y_{t+1} &= Wx_t + Ze_{t+1}
\end{aligned} (29)$$

where e_t is $k \times 1$. Assume that only y_t is observable.

Assume:

dim(yt) = dim(xt) (alternatively, assume that W has a left-inverse).
 All eigenvalues of Q and WQW^T are inside the unit circle.
 dim(yt) = dim(et) (alternatively, assume that Z is invertible).

Let the covariance structure of the observable y_t be $C_i = E(y_t y_{t-i})$, for

all *i*. C_i can be computed from the state space system (29) as

$$C_{0} = WQW^{T}C_{0}(WQW^{T})^{T} + ZZ^{T} + WUU^{T}W^{T}$$

- $WQW^{T}C_{0}(WQW^{T})^{T}$ (30)

$$C_1 = WQW^T C_0 + WUZ^T - WQW^T ZZ^T$$
(31)

$$C_i = (WQW^T)^{i-1}C_1, \quad \forall i > 1$$
 (32)

The MA representation for y_t from the model is

$$y_{t+1} = Ze_{t+1} + W \sum_{i=0}^{\infty} Q^i Ue_{t-1}$$
(33)

- Given the assumptions made, there are 2^k infinite order covariance equivalent MA representations for y_t with innovations e_t^i satisfying $E_t(e_t^i(e_t^i)^T) = I_k$. - The representation j is given by

$$y_{t+1} = (I - AL)^{-1} (D_j + B_j L) e_{t+1}^j$$

where A, B_j, D_j are given by

$$A = C_2 C_1^{-1} (34)$$

$$B_j = \bar{C}_1 (D_j^T)^{-1} \tag{35}$$

$$\bar{C}_1 = C_1 - AC_0 \tag{36}$$

$$\bar{C}_0 = C_0 - A C_0 A^T - A \bar{C}_1 - \bar{C}_1 A^T$$
 (37)

$$0 = (D_j D_j^T) (\bar{C}_1^T)^{-1} (D_j D_j^T) - \bar{C}_0 (\bar{C}_1^T)^{-1} (D D_j^T) + \bar{C}_1 \quad (38)$$

where C_i are the autocovariances of y_t .

Note 1) $D_j + D_j^c H_j$, where D_j^c is the Choleski decomposition of $D_j D_j^T$ and H_j an orthonormal matrix. With Choleski restrictions $H_j = I$, with long run and sign restrictions $H_j \neq H_{j'}, j \neq j'$.

Note 2) in the above set of equivalent MA, one is fundamental, the rest are not.

How do we choose among the 2^k representations we produce?

i) Drop all the representations with complex roots (not clear why).

ii) Drop all representations that do not satisfy certain additional restrictions. **Example 3** Permanent in come of section 6. Here there is only one obsrevables so there are only two MA representations, the fundamental one and the non-fundamental one. The impulse responses of the two representations are below. How do we choose between the two repesentations?



Why do we save? For future consumption! Thus, at some point in the future savings should reverse sign (addition theoretical restriction). Of the two repesentations only the

non-fundamental one implies that savings will drop at some horisons in the future, i.e. eliminate the fundamental one because it is inconsistent with theory.

- Look like an ex-post criteria !! Maybe people have utility from wealth. Wrong to choose the non-fundamental representation.

Example 4 Anticipated tax shocks (Leeper, et al. 2009). This model does not have unobservable controls but has a tax shock which is anticipated $T_t = \phi a_t + \epsilon_{t-2}$, where a_t is a technology shock. The solution to the model has the state space representation like (29) where $Q = \begin{bmatrix} \alpha & -\frac{\tau(1-\theta)}{1-\tau} & 0\\ 0 & 0 & 0\\ 0 & 1 & 0 \end{bmatrix}$, $U = \begin{bmatrix} 1 & -\frac{\tau\theta(1-\theta)}{1-\tau} & 0\\ 0 & 1 & 0\\ 0 & 0 & 0 \end{bmatrix}$, $W = \begin{bmatrix} 0 & 0 & 1\\ \alpha & -\frac{\tau(1-\theta)}{1-\tau} & 0\\ \alpha & \frac{\theta\tau}{1-\tau} & 0 \end{bmatrix}$, $Z = \begin{bmatrix} \psi & 0 & 0\\ 1 & -\frac{\tau(\theta 1-\theta)}{1-\tau} & 0\\ 0 & \frac{\tau\theta^2}{1-\tau} & 0 \end{bmatrix}$, and $x_t = [k_t, \epsilon_t, \epsilon_{t-1}]', e_t = (a_t, \epsilon_t, u_t)', y_t = \begin{bmatrix} 0 & \frac{\tau\theta^2}{1-\tau} & 0\\ 0 & \frac{\tau\theta^2}{1-\tau} & 0 \end{bmatrix}$

 (τ_t, k_t, c_t) where u_u is a an iid measurement error, $(\tau, \theta, , \alpha, \psi)$ are parameters.

The VARMA(1,1) representation for y_t is $y_{t+1} = WQW^T y_t + Ze_{t+1} + (WU - WQW^T Z)e_t$ (39)

With 3 observable variables there are $2^3 = 8$ covariance equivalent MA representations. The pairs B_j , D_j associated with these euivalent MA representations satisfy:

$$D_{j}D_{j}^{T} + B_{j}B_{j}^{T} = \begin{cases} \psi^{2}\sigma_{a}^{2} + \theta^{2} + (\frac{\sigma_{u}}{\kappa})^{2} & \psi\sigma_{a}^{2} + \kappa\theta(1-\theta) & \phi\sigma_{a}^{2} - \kappa\theta^{2} \\ \psi^{2}\sigma_{a}^{2} + \kappa\theta(1-\theta) & \sigma_{a}^{2} + \kappa^{2}(1+\theta^{2})(1-\theta)^{2} & \sigma_{a}^{2} - \kappa^{2}\theta(1-\theta)(1+\theta^{2}) \\ \psi\sigma_{a}^{2} - \kappa\theta^{2} & \sigma_{a}^{2} - \kappa^{2}\theta(1-\theta)(1+\theta^{2}) & \sigma_{a}^{2} + \kappa^{2}\theta^{2}(1+\theta^{2}) + \sigma_{u}^{2} \end{cases} \end{bmatrix}$$

$$B_{j}D_{j}^{T} = \begin{bmatrix} 0 & \kappa\theta^{2}(1-\theta) & -\kappa\theta^{3} - \frac{\sigma_{u}^{2}}{\kappa} \\ 0 & \kappa^{2}\theta(1-\theta)^{2} & -\kappa^{2}\theta^{2}(1-\theta) \\ 0 & -\kappa^{2}\theta^{2}(1-\theta) & \kappa^{2}\theta^{3} \end{bmatrix} \text{, where } \kappa = \frac{\tau}{1-\tau}.$$

With a standard parameterization, there are only 4 real values structural responses since $D_j D_j^T$ has a pair of complex eigenvalues.

Identify tax shocks and techology shocks using lower triangular Choleski (as detailed by the entries of the matrix Z).



How do you choose between the four remaining repesentations?

Note that responses to tax shocks are all similar in sign (except for consumption), differences is only in magnitude. Fundamental representation not that different from the three non-fundamental representations. Differences occur in response to technology shocks.

What kind of restrictions can we impose to eliminate representations?

1) Contribution of the identified measurement error shocks to variance decomposition of any variables should not exceed 30 percent (why 30 percent?)

2) Technology shocks should not be the main source of volatility of tax rates at long horizons. Exclude all representations generating decompositions where they account for more than 50 percent (Why shouldn't technology shocks explain more than 50 percent of the variance of tax rates?).

	Model One	Model Two	Model Three	Model Four
The average contr	ibutions on diff	erent horizons o	f identified measure	ment errors on variables
tax rate	0	34.82	0	14.78
capital	0	39.32	0	0.51
consumption	7.84	39.45	7.84	70.51
The ave	rage contributio	ons of technolog	ry on tax rate at diffe	rent horizons
	1.42	35.05	1.42	53.24
The contril	oution of techno	logy shocks on a	capital and consump	tion when $h = 1$
capital	0	37.55	79.11	71.01
consumption	0	48.01	83.23	0.09

From table decompositions 2 and 4 are eliminated. Note model 4 corresponds to the fundamental representation.

If we add:

3) The effect of techology shocks should be fast enough - so that technology shocks explain most of the variability of consumption and capital in short run (say larger than 30 percent). We are left with just one model.

• Interesting way to proceed, but difficult to justify restrictions in step 4 (choose representations that satisfy a-priori ideas about how the economy works).

• Important assumptions needed to derive all the equivalent MA representations.

• Cumbersome to apply in medium scale systems.

Aside: How do you estimate VARMA models?

$$A_0 y_t = A(\ell) y_{t-1} + M_0 u_t + M(\ell) u_{t-1}$$
(40)

 $A(\ell)$ is of order p_1 , $M(\ell)$ is of order p_2 . The standard way is to use ML (see e.g. Hamilton (1994)).

Problems:

- difficult to identify correctly the model.
- near cancellation of roots possible.

- likelihood has multiple peaks in correspondence of the multiplicity of covariance equivalent MA representations.

Alternatives: all based on Durbin (1960 and Hannan and Rissanen (1982)).

• Two step approach: step 1 running a AR and estimate the residuals; plug the estimated residuals in and estimate the resulting VARMA by OLS.

Model (stage 1):

$$y_t = \sum_i^q \Pi_i y_{t-i} + u_t$$

- q should be long enough to make u_t white noise.

- Typically set $q = 0.5 * T^{0.5}$ (to avoid non-invertible representations)

Model (stage 2):

$$y_t = (I - A_0)(y_t - \hat{u}_t) + A(\ell)y_{t-1} + M(\ell)\hat{u}_{t-1} + u_t$$

where $M_0 = A_0$, and \hat{u}_t are obtained at the first stage.

- All the regressors are observables, can use OLS.

Dufour and Jouini (2005) if q grows at the rate $T^{0.5}$ as $T \to \infty$ parameter estimation is consistent and convergence to asymptotic normality at a rate $T^{0.25}$ (slow convergence).

Other approach add a third step to improve the efficiency of the estimation (see Hannan and Kavalieris (1984) or iterate on the two steps (see Kapetanios (2003)) to improve the convergence rate.