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A New Proof Of The Maximum Principle

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Résumé / Abstract

Nous donnons une preuve nouvelle du principe de maximum pour les problèmes de contrôle optimal aux points terminaux fixés. Le cas où il y a des contraintes en forme d'inégalité est permis. Notre preuve utilise le théorème de l'enveloppe.

We offer a new proof of the maximum principle for optimal control problems with fixed endpoint. We allow for inequality constraints involving state variables and control variables. Our proof relies on an application of the envelope theorem.

Key Words: Maximum Principle, Envelope Theorem

Mots Clés: Principe de Maximum, Théorème de l'Enveloppe

JEL Classification: C61

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1 Introduction

The purpose of this note is to offer a new and simple proof of the maximum principle, using the envelope theorem¹. A number of authors have provided proofs of the maximum principle using the idea that a small deviation from the optimal path of the control variable must have a negative impact on the value of the objective function (see, for example, Kamien and Schwartz, 1991, pp 124-7, Leonard and Long, 1992, pp 161-3). The proof by Kamien and Schwartz relies on the assumption of a “free value of the state variable at the terminal point” (p.124) while Leonard and Long, dealing with a *fixed* value of the state variable at the terminal point, assume the existence of a class of deviation function with some special properties. The proof that we offer below does not rely on either of these assumptions².

2 A proof based on the envelope theorem

Let $k = (k_1, \dots, k_n)$ denote the vector of state variables and $z = (z_1, \dots, z_m)$ denote the vector of control variables. The transition equation, in vector notation, is

$$\dot{k} = g(k, z, t) \quad (1)$$

where $g(\cdot)$ have continuous partial derivatives. Given k and t , the control vector is restricted to belong to some set $A(k, t)$. We assume that this set can be described by

$$A(k, t) = \{z : \phi(k, z, t) \geq 0\}$$

where $\phi = (\phi_1, \dots, \phi_s)$ is a vector of s differentiable functions. The objective function is

$$\max \int_0^T U(k, z, t) dt \quad (2)$$

subject to (1), $z \in A(k, t)$, and the boundary conditions $k(0) = k_0$ (given) and $k(T) = k_T$ (fixed).

In the special case where it is possible to invert (1) to obtain $z = h(k, \dot{k}, t)$, one can substitute for z and apply the calculus of variations. In general, however, such inversion is not possible (for example, when the number of control variables exceed the number of state variables). In this note we deal with the general case.

Let $(k^*(t), z^*(t))$ be an optimal time path, i.e., a solution to problem (2). Then at any time t , given $k^*(t)$ and $\dot{k}^*(t)$, it must be the case that $z^*(t)$ solves the static problem

$$\max_z U(k^*(t), z, t) \quad (3)$$

¹After completing this paper, we discovered that a similar proof is offered in Dana and Le Van (2001). The main feature that distinguishes our approach from theirs is our direct application of the envelope theorem, a tool that many economic researchers have found useful.

²Other economists, such as Arrow and Kurz (1970), Silberberg (1990, pp. 620-621), proved the maximum principle by using the Hamilton-Jacobi-Bellman equation. Such an approach relies on the assumption of a twice-differentiable value function. Our proof does not rely on that assumption.

subject to the equality constraint

$$g(k^*(t), z, t) - \dot{k}^*(t) = 0 \quad (4)$$

and the inequality constraint

$$\phi(k^*(t), z, t) \geq 0. \quad (5)$$

We apply the Kuhn-Tucker theory to the static problem (3). Here, we omit the asterisk to lighten notation. We assume that the constraint qualifications hold (see, for example, Takayama, 1985, p 101). Then there exists a vector (λ, μ) with which we can form the Lagrangian function

$$\begin{aligned} L(z, \lambda, \mu; k(t), \dot{k}(t), t) = \\ U(k(t), z, t) + \lambda [g(k(t), z, t) - \dot{k}(t)] + \mu \phi(k(t), z, t) \end{aligned} \quad (6)$$

and obtain the necessary conditions:

$$L_z = U_z + \lambda g_z + \mu \phi_z = 0 \quad (7)$$

$$L_\mu = \phi(k(t), z, t) \geq 0, \mu \geq 0, \mu \phi(k(t), z, t) = 0 \quad (8)$$

$$L_\lambda = g(k(t), z, t) - \dot{k}(t) = 0 \quad (9)$$

The solution to this system of equation is denoted by $z = z(k(t), \dot{k}(t), t)$, $\lambda = \lambda(k(t), \dot{k}(t), t)$, $\mu = \mu(k(t), \dot{k}(t), t)$. Now, by appealing to the Envelope Theorem (see, for example, Takayama, 1985, p 138) we have

$$\begin{aligned} \frac{\partial}{\partial k(t)} U(k(t), z(k(t), \dot{k}(t), t), t) &= \frac{\partial}{\partial k(t)} L(z, \lambda, \mu; k(t), \dot{k}(t), t) \\ &= U_k + \lambda g_k + \mu \phi_k \end{aligned} \quad (10)$$

$$\begin{aligned} \frac{\partial}{\partial \dot{k}(t)} U(k(t), z(k(t), \dot{k}(t), t), t) &= \frac{\partial}{\partial \dot{k}(t)} L(z, \lambda, \mu; k(t), \dot{k}(t), t) \\ &= -\lambda(k(t), \dot{k}(t), t) \end{aligned} \quad (11)$$

Now, let us return to the dynamic optimization problem (2), with $z = z(k(t), \dot{k}(t), t)$. That is, we seek to maximize

$$\int_0^T U(k(t), z(k(t), \dot{k}(t), t), t) dt \equiv \int_0^T F(k(t), \dot{k}(t), t) dt$$

subject to the boundary conditions are $k(0) = k_0$ (given) and $k(T) = k_T$ (fixed). The following Euler-Lagrange condition is necessary for an optimal solution:

$$\frac{d}{dt} [F_k] = \frac{\partial F}{\partial k} \quad (12)$$

Substituting (11) into the left-hand side of (12) and (10) into the right-hand side of (12), we get:

$$-\frac{d}{dt}\lambda(k^*(t), \dot{k}^*(t), t) = U_k + \lambda g_k + \mu \phi_k \quad (13)$$

Let us we define

$$\lambda^*(t) = \lambda(k^*(t), \dot{k}^*(t), t) \text{ and } \mu^*(t) = \mu(k^*(t), \dot{k}^*(t), t)$$

and

$$\mathcal{H}(k, z, \lambda^*, t) = U(k, z, t) + \lambda^* g(k, z, t) \quad (14)$$

$$\mathcal{L}(k, z, \lambda^*, \mu^*, t) = \mathcal{H}(k, z, \lambda^*, t) + \mu^* \phi(k, z, \lambda^*, \mu^*, t) \quad (15)$$

Then, from the definitions (14)-(15), the equations (7)-(9) and (13), we obtain the necessary conditions that constitute the maximin principle:

$$\frac{\partial \mathcal{L}}{\partial z} = \frac{\partial \mathcal{H}}{\partial z} + \mu^* \frac{\partial \phi}{\partial z} = 0$$

$$\dot{\lambda} = -\frac{\partial \mathcal{L}}{\partial k}$$

$$\dot{k} = \frac{\partial \mathcal{L}}{\partial \lambda}$$

This concludes our proof of the maximum principle.

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