M.A./M.Sc. 1st Semester Examination, 2019 ECONOMICS

PAPER -ECO-103(GR.-A+B)

Full Marks: 40

Time: 2 hours

The figures in the right-hand margin indicate marks

Candidates are required to give their answers in their own words as far as practicable

Illustrate the answers wherever necessary

Write the answers to Questions of each Units in separate books wherever necessary

GROUP - A

[Marks : 20]

1. Answer any two questions:

 2×2

(a) Is nonlinear programming technique an improvement over linear programming?

Justify.

(b) Consider the following nonlinear programming problem and write the Kuhn-Tucker condition for this problem

Max
$$Z = xy$$

subject to $P_x X + P_y y \le M$
 $x \le 40$
and $x_1, x_2 \ge 0$.

- (c) Define cartesian product of sets.
- (d) Distinguish between one-to-one and onto-mapping.
- 2. Answer any two questions:

 4×2

- (a) What is constraint qualification? What are its requirements?
- (b) Give suitable examples of the prevalence of nonlinearity in economics.
- (c) What are test vectors and qualifying arc?
- (d) State and proof De' Morgan's law.

3. Answer any one questions:

 8×1

- (a) Derive the Kuhn-Tucker condition for a non-linear programming problem of maximization type.
- (b) Distinguish between Kuhn-Tucker sufficiency theorem and Arrow-Enthoven sufficiency theorem for a maximization problem.

GROUP - B

[Marks : 20]

4. Answer any two questions:

 2×2

- (a) What is functional?
- (b) Write any two types of variable terminal points.
- (c) What is dominant strategy?
- (d) What do you mean by Bayesian games?
- 5. Answer any *two* questions: 4×2
 - (a) Explain mixed strategy equilibrium of game.

- (b) Explain different problems of Nash equilibrium with suitable examples.
- (c) Explain the saddle path in phase diagram analysis.
- (d) How can you find solution for dynamic optimization problem involving discounting?
- 6. Answer any *one* questions: 8×1
 - (a) Define and explain subgame perfect equilibrium with suitable example.
 - (b) Solve the following dynamic optimization problem using Hamiltonian identifying state and control variables:

$$\int_0^T (K - aK^2 - I^2) dt$$

$$K' = I - \delta K$$

$$K(0) = K_0.$$