

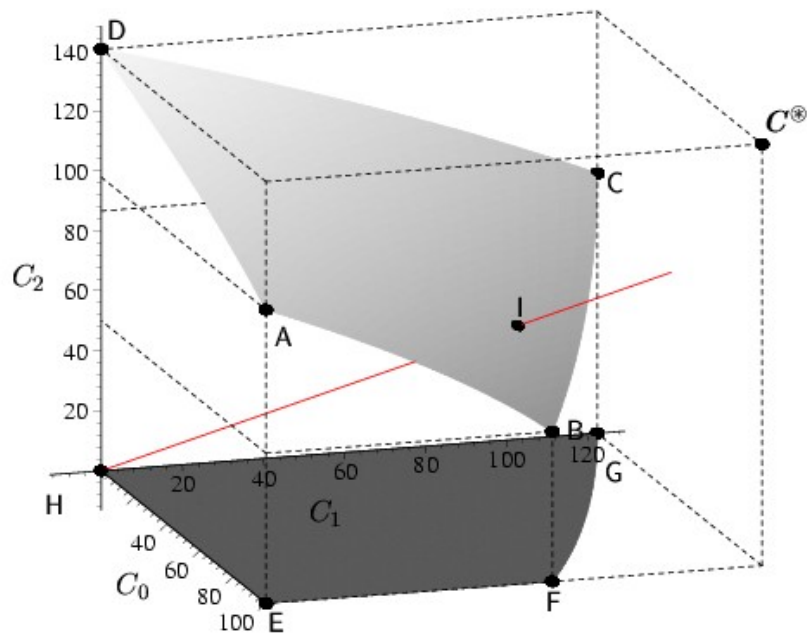
Supplement to

Efficiency versus Sustainability

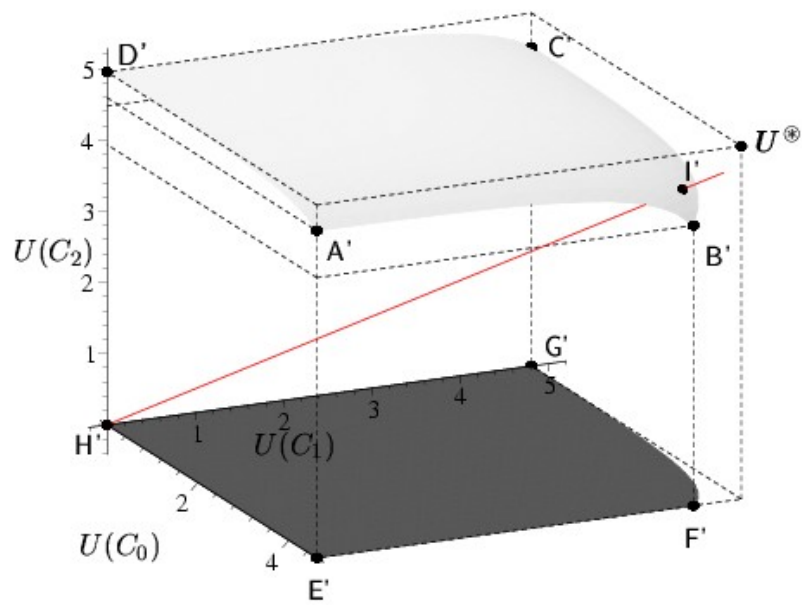
by Bodo Glaser

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(a) Control Space



(b) Objective Space

Figure 6.5: Surface of efficient trajectories in the 3-period model

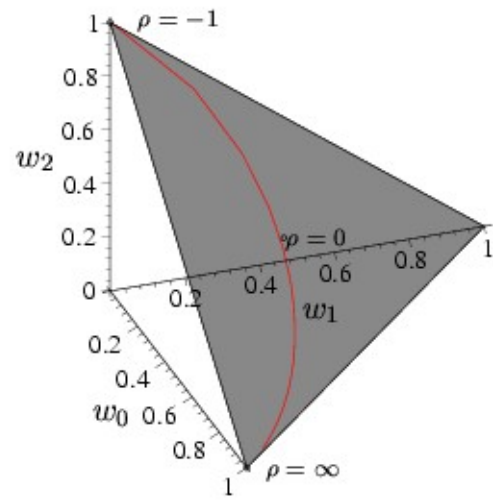


Figure 6.11: Weighting scheme 'discounting' as a subset of all admissible normed weights

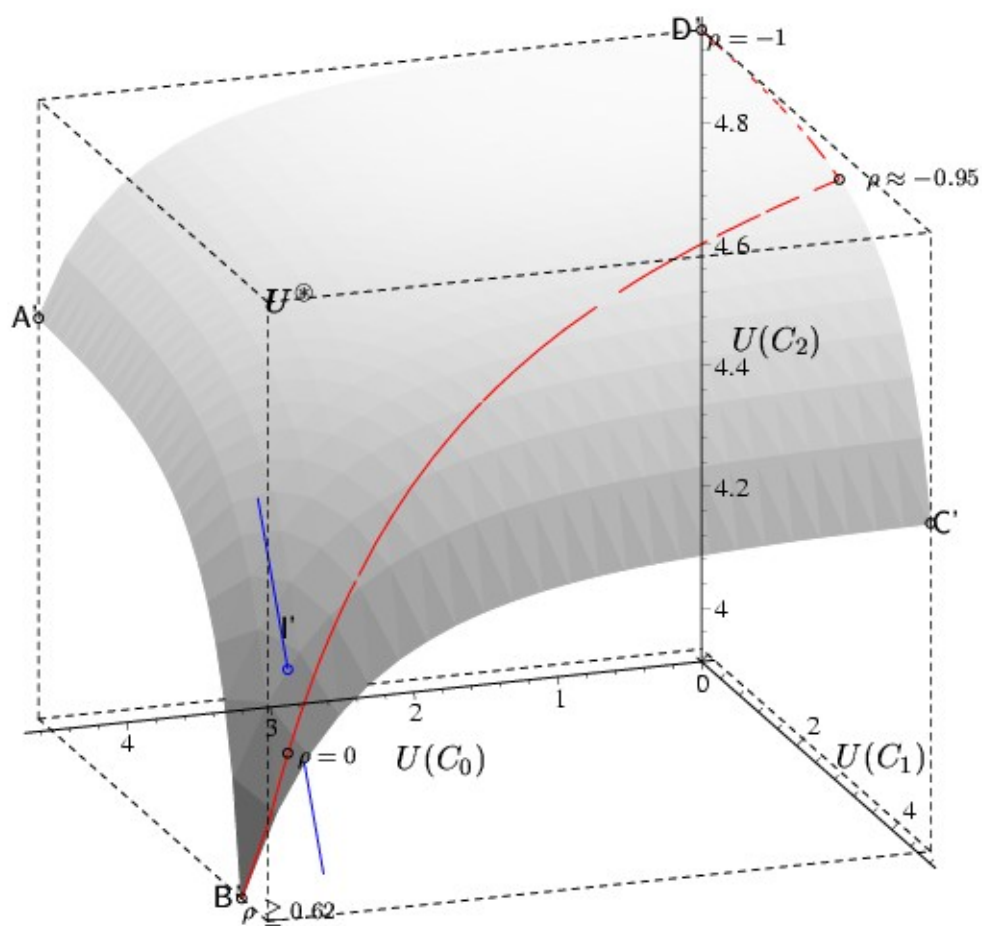


Figure 6.12: Compromise-optimal utility trajectories in the 3-period 'weighted sum' model depending on time-preference rate ρ

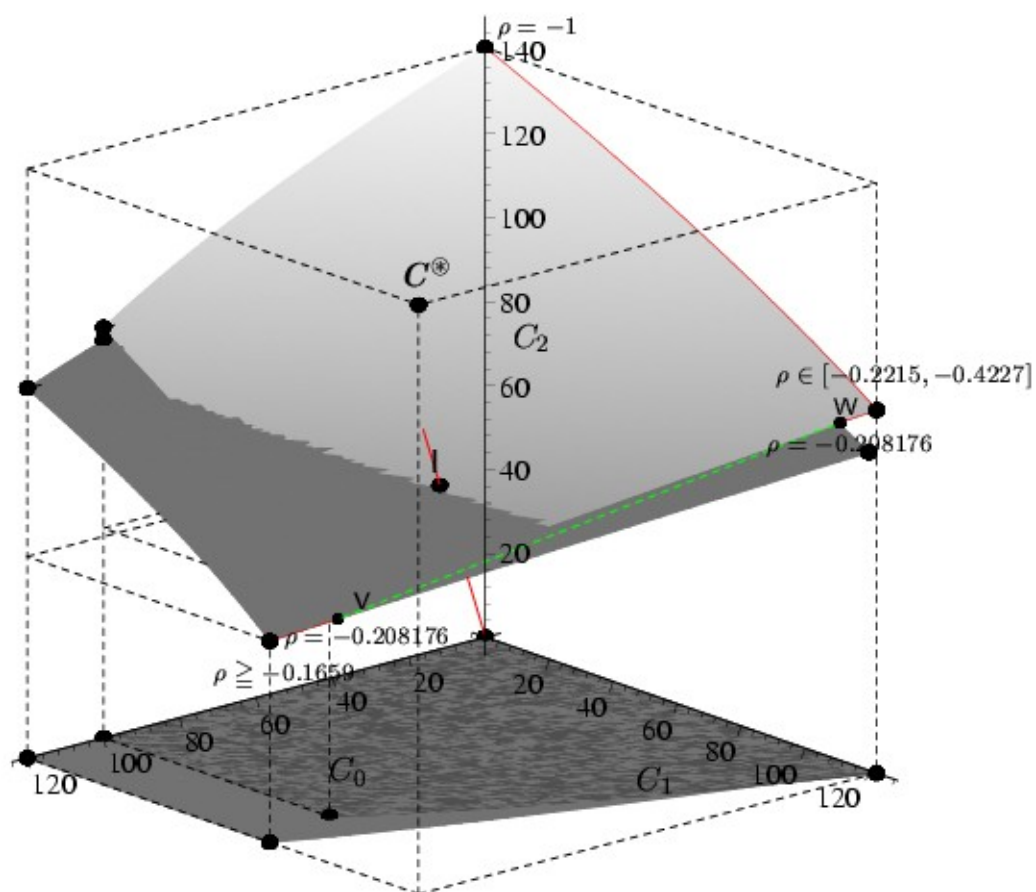


Figure 6.13: Compromise-optimal consumption trajectories in the 3-period 'weighted sum' model with nonconvex objective set parameterized over time-preference rate ρ

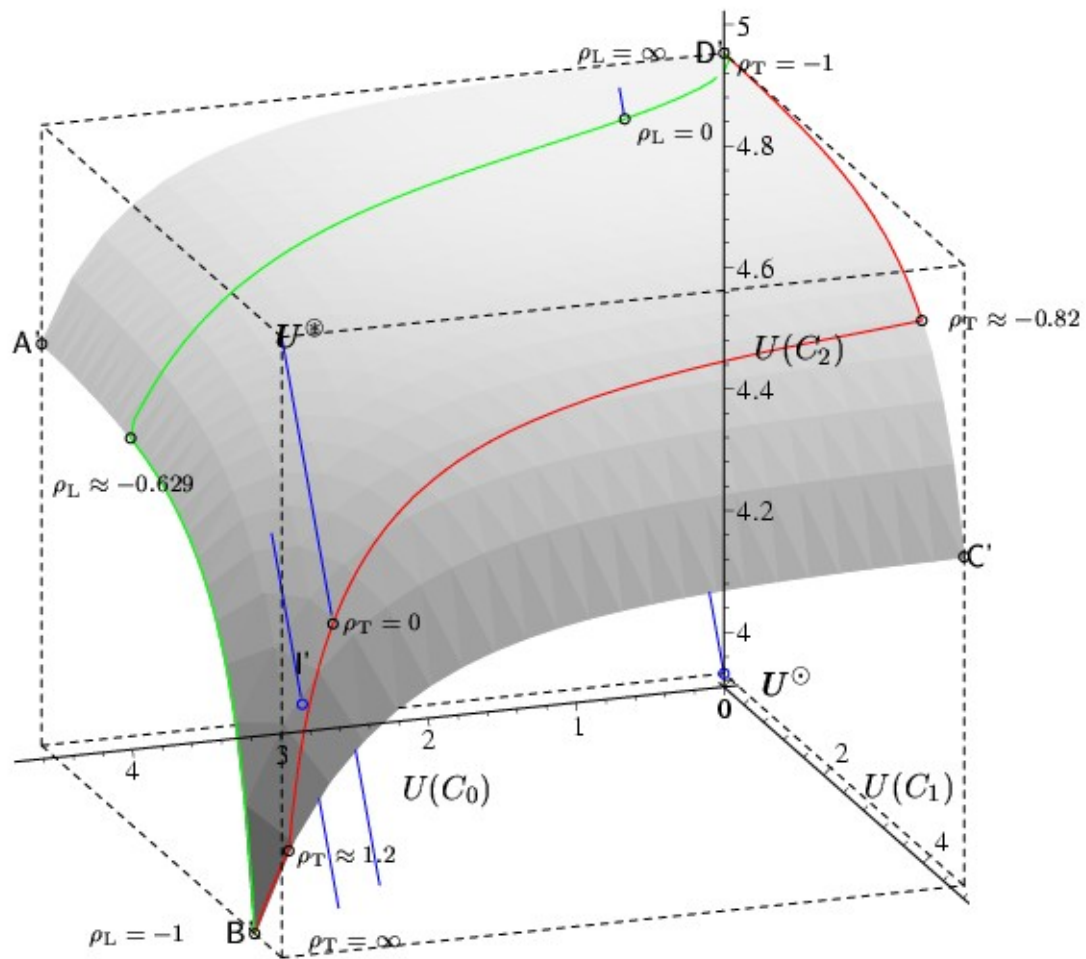
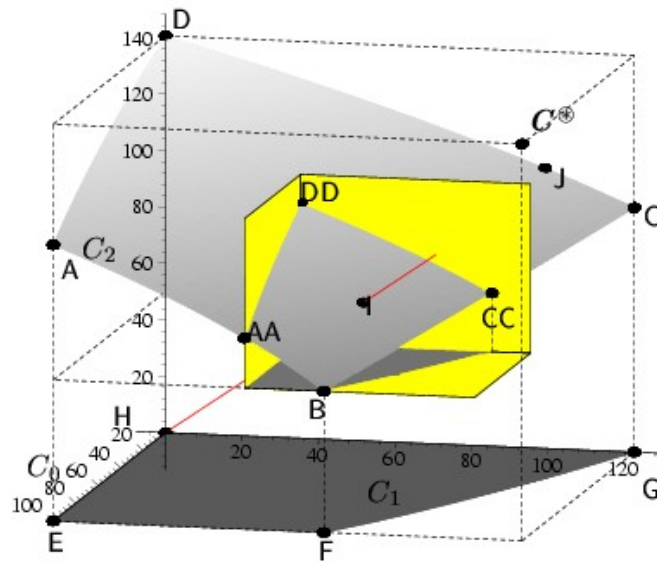
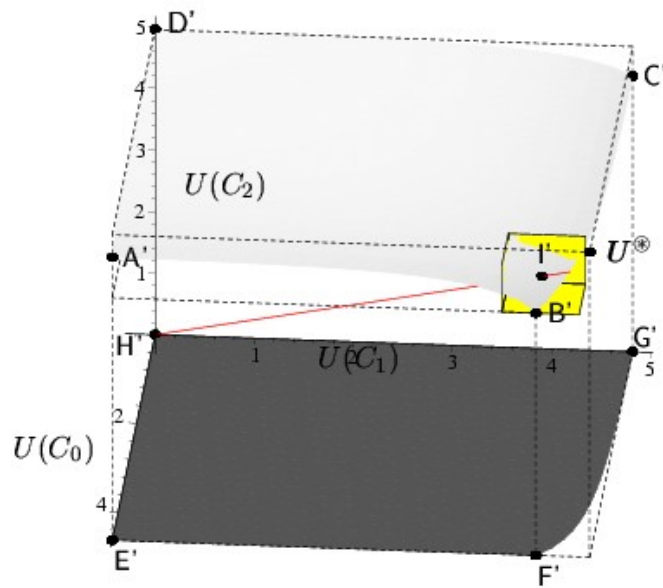


Figure 6.14: Compromise-optimal utility trajectories with TCHEBY-CHEFF-norm and LEONTIEF-N-distance depending on time-preference rates ρ_T and ρ_L

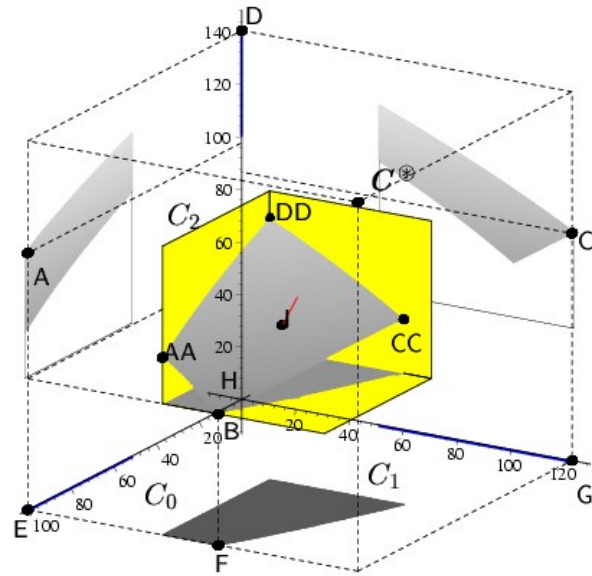


(a) Objective Space for $U(C) = C$

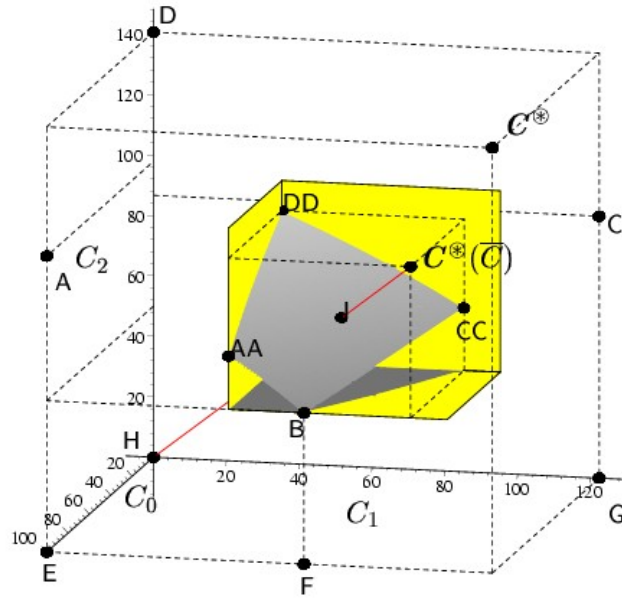


(b) Objective Space for $U(C) = \ln(C + 1)$

Figure 6.15: 3-period model with minimum consumption value \bar{C} or, respectively, minimum utility value \bar{U}



(a) Objective space for $(DDM_{Rob,SwM}^B)$ with $\tilde{C} = 0$



(b) Objective space for $(DDM_{Rob,SwM,2}^B)$

Figure 6.18: 3-period model of satisficing with maximizing behavior given a minimum consumption value $\bar{C} = 50$

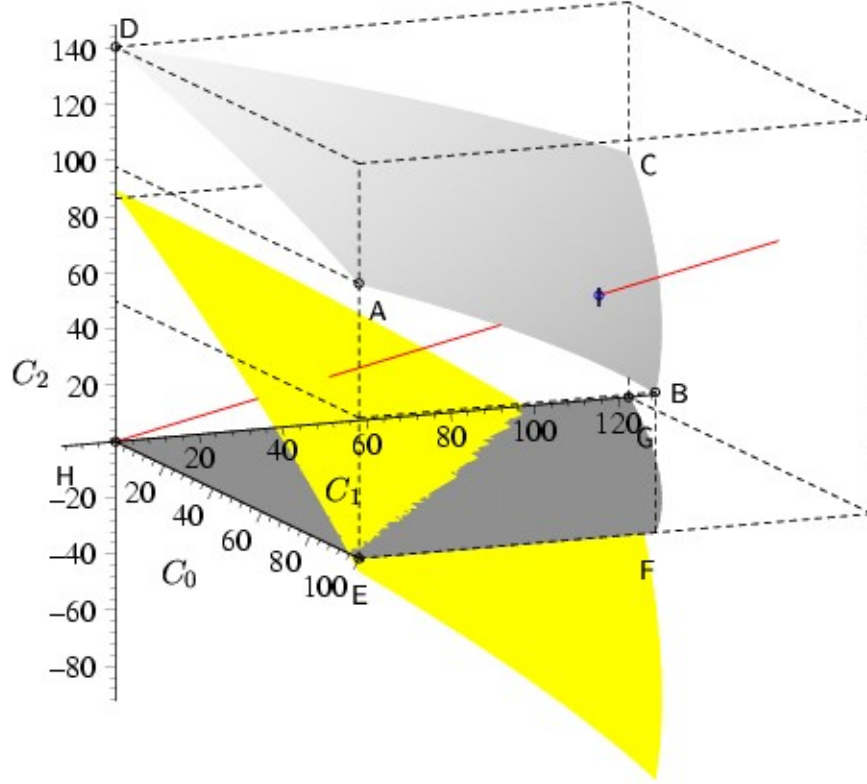


Figure 7.1: Control space of $(DDM_{Rob,i}^{A \times B})$ showing all admissible control trajectories and the iso- K_3 surface for $\bar{K}_3 = 150$

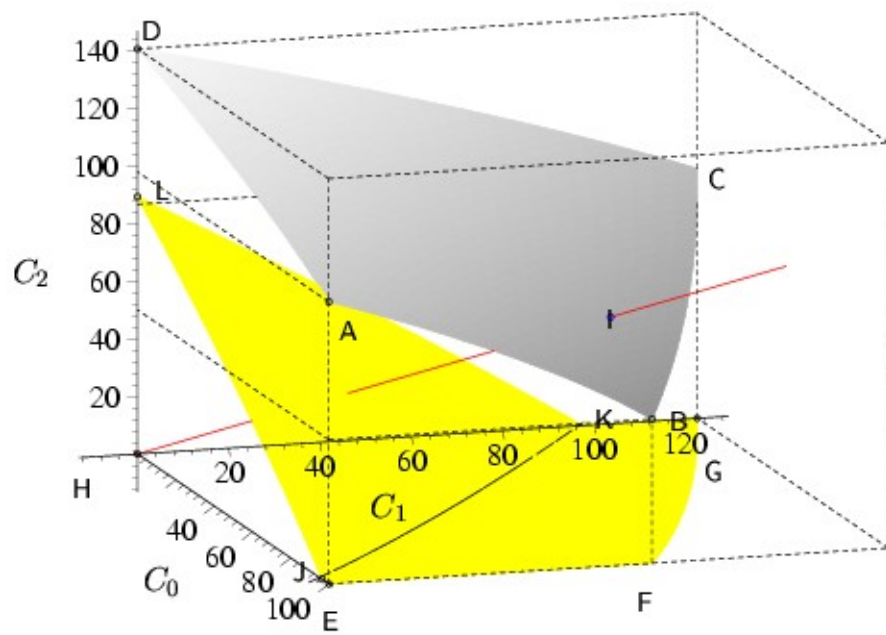


Figure 7.2: Control space of $(DDM_{Rob,ii}^{A \times B})$ showing all AB-efficient control trajectories

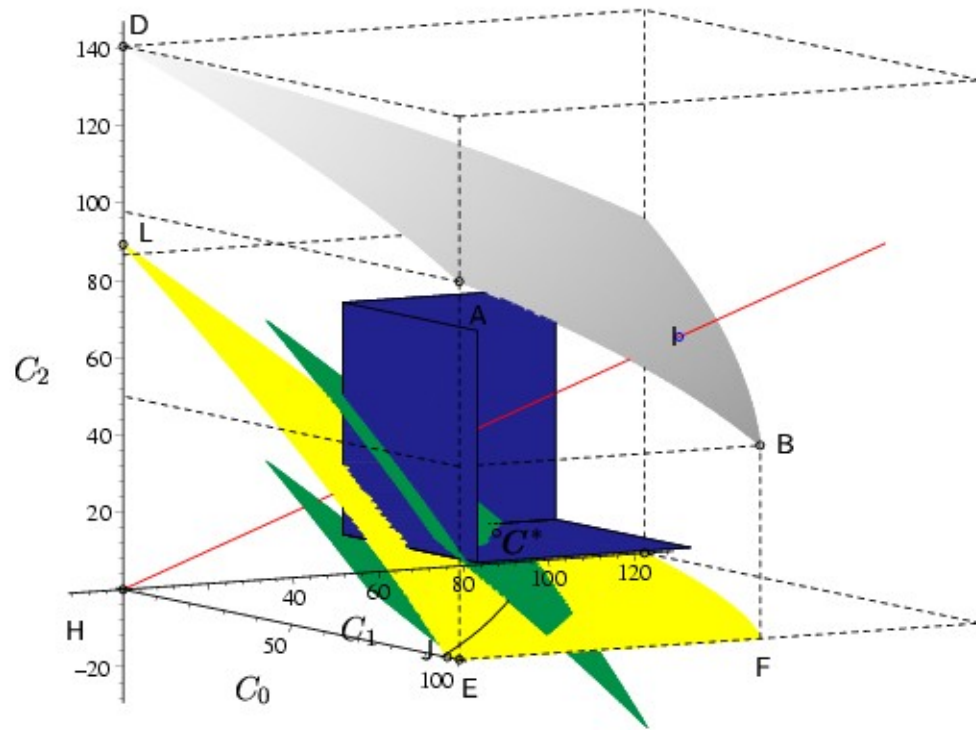


Figure 7.3: Test of AB-efficiency in the control space of $(DDM_{Rob,ii}^{A \times B})$

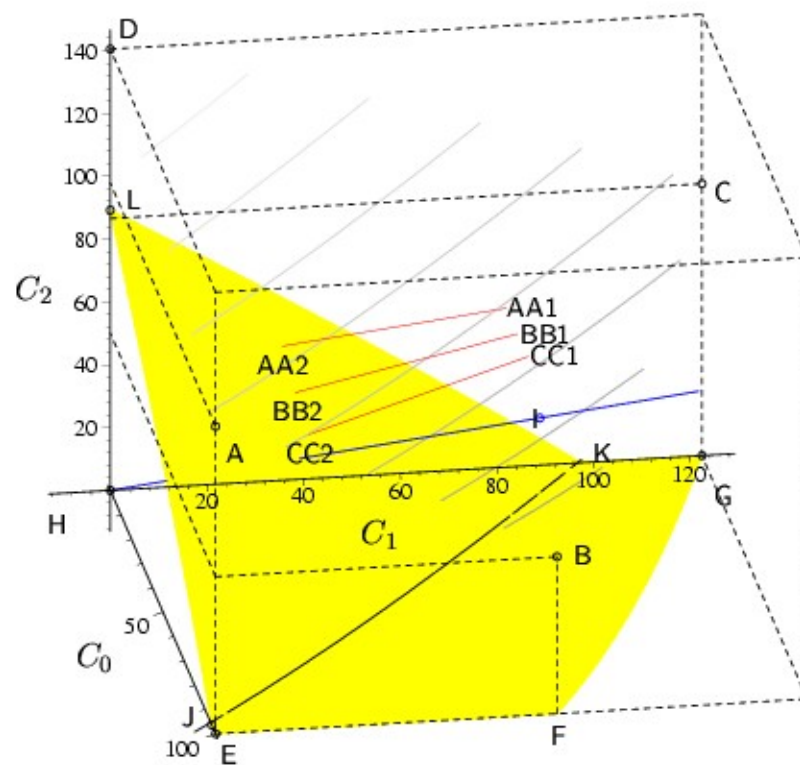


Figure 7.4: Compromise solutions in the control space of $(\text{DDM}_{\text{Rob},ii}^{A \times B})$

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