

we get the  $n \times m$  system

$$\begin{aligned} \frac{\partial J}{\partial x_1}(u) + \lambda_1 \frac{\partial \varphi_1}{\partial x_1}(u) + \cdots + \lambda_m \frac{\partial \varphi_m}{\partial x_1}(u) &= 0 \\ &\vdots \\ \frac{\partial J}{\partial x_n}(u) + \lambda_1 \frac{\partial \varphi_1}{\partial x_n}(u) + \cdots + \lambda_m \frac{\partial \varphi_m}{\partial x_n}(u) &= 0, \end{aligned}$$

and it is important to note that the matrix of this system is the *transpose* of the Jacobian matrix of  $\varphi$  at  $u$ . If we write  $\text{Jac}(\varphi)(u) = ((\partial \varphi_i / \partial x_j)(u))$  for the Jacobian matrix of  $\varphi$  (at  $u$ ), then the above system is written in matrix form as

$$\nabla J(u) + (\text{Jac}(\varphi)(u))^T \lambda = 0,$$

where  $\lambda$  is viewed as a column vector, and the Lagrangian is equal to

$$L(u, \lambda) = J(u) + (\varphi_1(u), \dots, \varphi_m(u))\lambda.$$

The beauty of the Lagrangian is that the constraints  $\{\varphi_i(v) = 0\}$  have been incorporated into the function  $L(v, \lambda)$ , and that the necessary condition for the existence of a constrained local extremum of  $J$  is reduced to the necessary condition for the existence of a local extremum of the *unconstrained*  $L$ .

However, one should be careful to check that the assumptions of Theorem 40.2 are satisfied (in particular, the linear independence of the linear forms  $d\varphi_i$ ).

**Example 40.1.** For example, let  $J: \mathbb{R}^3 \rightarrow \mathbb{R}$  be given by

$$J(x, y, z) = x + y + z^2$$

and  $g: \mathbb{R}^3 \rightarrow \mathbb{R}$  by

$$g(x, y, z) = x^2 + y^2.$$

Since  $g(x, y, z) = 0$  iff  $x = y = 0$ , we have  $U = \{(0, 0, z) \mid z \in \mathbb{R}\}$  and the restriction of  $J$  to  $U$  is given by

$$J(0, 0, z) = z^2,$$

which has a minimum for  $z = 0$ . However, a “blind” use of Lagrange multipliers would require that there is some  $\lambda$  so that

$$\frac{\partial J}{\partial x}(0, 0, z) = \lambda \frac{\partial g}{\partial x}(0, 0, z), \quad \frac{\partial J}{\partial y}(0, 0, z) = \lambda \frac{\partial g}{\partial y}(0, 0, z), \quad \frac{\partial J}{\partial z}(0, 0, z) = \lambda \frac{\partial g}{\partial z}(0, 0, z),$$

and since

$$\frac{\partial g}{\partial x}(x, y, z) = 2x, \quad \frac{\partial g}{\partial y}(x, y, z) = 2y, \quad \frac{\partial g}{\partial z}(0, 0, z) = 0,$$