# Lectures on Parametric Optimization: An Introduction 

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## 1. Parametric equations

Consider the non-parametric equation: Solve

$$
F(x):=x^{2}-2 x-1=0
$$

with solutions $x_{1,2}=1 \pm \sqrt{2}$.
The parametric version is: For $t \in \mathbb{R}$ find a solution $x=x(t)$ of
(1) $\quad F(x, t):=x^{2}-2 t^{2} x-t^{4}=0$

The solutions are

$$
x_{1,2}(t)=t^{2} \pm \sqrt{2} t^{2}=t^{2}(1 \pm \sqrt{2})
$$

Ex. 1 Sketch the solution curve in the $(x, t)$ space.

At $\bar{t}=0$ with solution $\bar{x}=0$ we find for the gradient of $F$

$$
\nabla F(\bar{x}, \bar{t})=\binom{2 x-2 t^{2}}{-4 t x-4 t^{3}}_{\bar{x}, \bar{t}}=\binom{0}{0} .
$$

Rule. The solution set of $F(x, t)=0$ where $\overline{F: \mathbb{R}^{2}} \rightarrow \mathbb{R}$ is "normally" (locally) given by a one-dimensional solution curve $(x(t), t)$.
However at points $(\bar{x}, \bar{t})$ where $\nabla F(\bar{x}, \bar{t})=$ 0 holds the solution set has a singularity(such as a bifurcation or a nonsmoothness).

Two versions of the Implicit Function Theorem
We consider systems of $n+p$ equations in $n$ variables:
$F(x, t)=0 \quad$ where $\quad F: \mathbb{R}^{n} \times \mathbb{R}^{p} \rightarrow \mathbb{R}^{n}$. The Implicit Function Theorem (IFT) makes a statement on the structure of the solution set in the "normal" situation.

Theorem 1. (IFT for one equation)
Let $F: \mathbb{R}^{k} \rightarrow \mathbb{R}$ be a $C^{1}$-function. Suppose for $\bar{y} \in \mathbb{R}^{k}$ we have $F(\bar{y})=0$ and $\nabla F(\bar{y}) \neq 0$. Then near $\bar{y}$ the solution set $S(F):=\left\{y \in \mathbb{R}^{k} \mid F(y)=0\right\}$ is a $C^{1}$ manifold of dimension $k-1$. Moreover at $\bar{y}$

$$
\nabla F(\bar{y}) \perp S(F)
$$

and the gradient $\nabla F(\bar{y})$ points into the region where $F(y)>F(\bar{y})$.

Ex. 2 Give a geometrical sketch of the statement.

Theorem 2. (General version of the IFT) Let $F: \mathbb{R}^{n} \times \mathbb{R}^{p} \rightarrow \mathbb{R}^{n}$ be a $C^{1}$-function $F(x, t)$ with $(x, t) \in \mathbb{R}^{n} \times \mathbb{R}^{p}$. Suppose for $(\bar{x}, \bar{t}) \in \mathbb{R}^{n} \times \mathbb{R}^{p}$ we have $F(\bar{x}, \bar{t})=0$ and the matrix $\nabla_{x} F(\bar{x}, \bar{t})$ is nonsingular. Then in a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ the solution set $S(F):=\{(x, t) \mid F(x, t)=0\}$ is described by a $C^{1}$-function $x: U_{t}(\bar{t}) \rightarrow \mathbb{R}$ such that $x(\bar{t})=\bar{x}$ and

$$
F(x(t), t)=0 \quad \text { for } t \in U_{t}(\bar{t}) .
$$

(So, locally, $S(F)$ is a $p$ dimensional $C^{1}$ manifold.) Moreover the gradient $\nabla x(t)$ is given by $\left(t \in U_{t}(\bar{t})\right)$
$\nabla x(t)=-\left[\nabla_{x} F(x(t), t)\right]^{-1} \nabla_{t} F(x(t), t)$.
Proof. See e.g., [7]. Note that if $x(t)$ is a $C^{1}$-function satisfying $F(x(t), t)=0$ then by differentiation wrt. $t$ we find

$$
\nabla_{x} F(x(t), t) \nabla x+\nabla_{t} F(x(t), t)=0 .
$$

## 2. Parametric unconstrained OPTIMIZATION

2.1. Non-parametric minimization. We assume that $f: \mathbb{R}^{n} \rightarrow \mathbb{R}$ is a $C^{2}$-function. The point $\bar{x} \in \mathbb{R}^{n}$ is a local minimizer of $f$ if there is some $\varepsilon>0$ such that

$$
f(\bar{x}) \leq f(x) \quad \forall x, \quad\|x-\bar{x}\|<\varepsilon .
$$

It is called a strict local minimizer if:
$f(\bar{x})<f(x) \forall x \neq \bar{x},\|x-\bar{x}\|<\varepsilon$.
Theorem 3. (Necessary and sufficient optimality conditions) (see e.g., [4])
(a) If $\bar{x}$ is a local minimizer of $f$ then
$\nabla f(\bar{x})=0$ and $\nabla^{2} f(\bar{x}) \geq 0$ (pos. semidef.)
(b) If $\bar{x}$ satisfies
$\nabla f(\bar{x})=0$ and $\nabla^{2} f(\bar{x})>0$ (pos. definite)
then $\bar{x}$ is a strict local minimizer of $f$.
2.2. Parametric minimization. Let $f(x, t)$ be a $C^{2}$ function, $f: \mathbb{R}^{n} \times T \rightarrow \mathbb{R}$, where $T \subset \mathbb{R}^{p}$ is open. We consider the parametric problem: for $t \in T$ find a (local) solution $x=x(t)$ of
(2) $\quad P(t)$
$\min _{x \in \mathbb{R}^{n}} f(x, t)$
$x \in \mathbb{R}^{n}$

To solve this problem, for $t \in T$, we have to find solutions $x$ of the critical point equation
(3) $\quad F(x, t):=\nabla_{x} f(x, t)=0$.

The next examples show the possible bad behavior.
Ex. 3 For

$$
P(t): \quad \min f(x, t):=\frac{1}{3} x^{3}-t^{2} x
$$

the minimizer is given by $x(t)=|t|$ with minimal value $v(t):=f(x(t), t)=-\frac{2}{3}|t|^{3}$.

## Ex. 4 For

$P(t): \quad \min f(x, t):=\frac{1}{3} x^{3}-t^{2} x^{2}-t^{4} x$
the critical points are given by the curves $x_{1,2}(t)=t^{2}(1 \pm \sqrt{2})$ and the minimizer by $x_{1}(t)$.

Rule. The following appears:

- The value function $v(t)=f(x(t), t)$ may behave "smoother" than the minimizer function $x(t)$.
- A singular behavior appears at solution points $(\bar{x}, \bar{t})$ of $\nabla_{x} f(x, t)=0$ where the matrix $\nabla_{x}^{2} f(\bar{x}, \bar{t})$ is singular.

Ex. 5 Check the singular behavior for the examples Ex. 3 and Ex. 4 .

The next theorem describes the situation near a non-singular solution $(\bar{x}, \bar{t})$ of (3).

## Theorem 4. (local stability result) Let $\bar{x}$

 be a solution of $P(\bar{t}), \bar{t} \in T$, such that$\nabla_{x} f(\bar{x}, \bar{t})=0$ and $\nabla_{x}^{2} f(x, t)>0$ (pos. def.).
Then in a neighborhood $U_{t}(\bar{t})$ there is a $C^{1}$-function $x: U_{t}(\bar{t}) \rightarrow \mathbb{R}^{n}$ such that $x(\bar{t})=$ $\bar{x}$ and for any $t \in U_{t}(\bar{t}), x(t)$ is a strict local minimizer of $P(t)$. Moreover for $t \in U_{t}(\bar{t})$,
$\nabla x(t)=-\left[\nabla_{x}^{2} f(x(t), t)\right]^{-1} \nabla_{x t}^{2} f(x(t), t)$,
and the value function $v(t):=f(x(t), t)$ is a $C^{2}$-function with

$$
\nabla v(t)=\nabla_{t} f(x(t), t)
$$

and

$$
\nabla^{2} v(t)=\nabla_{t x}^{2} f(x(t), t) \nabla x(t)+\nabla_{t}^{2} f(x(t), t)
$$

Proof. Apply the IFT to the equation $\nabla_{x} f(x, t)=0$.
Rem. Note that $x(t)$ is $C^{1}$ but $v(t)$ is $C^{2}$.

## 3. Parametric constraint OPTIMIZATION

3.1. Non-parametric programs. Consider nonlinear programs:
(4)
$P: \min _{x \in \mathbb{R}^{n}} f(x)$ s.t. $x \in \mathcal{F}:=\left\{x \mid g_{j}(x) \leq 0, j \in J\right\}$
with index set $J=\{1, \ldots, m\}$. The set $\mathcal{F}$ is called feasible set.
Def. A point $\bar{x} \in \mathcal{F}$ is called local minimizer of order $s=1$ or $s=2$ if there are constants $c, \varepsilon>0$ such that
$f(x)-f(\bar{x}) \geq c\|x-\bar{x}\|^{s} \quad \forall x \in \mathcal{F},\|x-\bar{x}\|<\varepsilon$.
It is a global minimizer if $f(x) \geq f(\bar{x})$ holds $\forall x \in \mathcal{F}$.

For $\bar{x} \in \mathcal{F}$ we introduce the active index set

$$
J_{0}(\bar{x})=\left\{j \in J \mid g_{j}(\bar{x})=0\right\}
$$

and the Lagrangian function

$$
L(x, \mu)=f(x)+\sum_{j \in J_{0}(\bar{x})} \mu_{j} g_{j}(x) .
$$

The coefficients $\mu_{j}$ are called Lagrangian multipliers. We say that the Linear Independence constraint qualification (LICQ) is satisfied at $\bar{x} \in \mathcal{F}$ if
$\nabla g_{j}(\bar{x}), j \in J_{0}(\bar{x})$, are linearly independent. The next theorem gives the famous Karush-Kuhn-Tucker (KKT) sufficient optimality conditions.

Theorem 5. (Sufficient optimality conditions)
Let $\bar{x} \in \mathcal{F}$ satisfy LICQ.
(a) (Order one) Let with multipliers $\bar{\mu}_{j}$ the KKT condition
(5)

$$
\nabla_{x} L(\bar{x}, \bar{\mu})=\nabla f(\bar{x})+\sum_{j \in J_{0}(\bar{x})} \bar{\mu}_{j} \nabla g_{j}(\bar{x})=0
$$

$\bar{\mu}_{j} \geq 0, j \in J_{0}(\bar{x})$, be satisfied such that $\bar{\mu}_{j}>0, \forall j \in J_{0}(\bar{x})$ (Strict complement. (SC)) and $\left|J_{0}(\bar{x})\right|=n$. Then $\bar{x}$ is a local minimizer of $(P)$ of order $s=1$.
(b) (Order two) Let with multipliers $\bar{\mu}_{j}$ the KKT condition (5) be satisfied such that (SC) holds and the second order condition (SOC)
SOC: $\quad d^{T} \nabla_{x}^{2} L(\bar{x}, \bar{\mu}) d>0 \forall d \in T_{\bar{x}} \backslash\{0\}$ where $T_{\bar{x}}$ is the tangentspace $T_{\bar{x}}=\left\{d \mid \nabla g_{j}(\bar{x}) d=0, j \in J_{0}(\bar{x})\right\}$. Then $\bar{x}$ is a local minim. of $(P)$ of order $s=2$.

Ex. 6 Show that the point $\bar{x}=0$ is the minimizer of order $s=1$ of the problem $\min x_{2}$ s.t. $e^{-x_{1}}-x_{2}-1 \leq 0, x_{1}-x_{2} \leq 0$

Rem. The KKT conditions can also be given in the equivalent (global) form:

$$
\text { (6) } \begin{aligned}
\nabla f(x)+\sum_{j \in J} \mu_{j} \nabla g_{j}(x) & =0 \\
\mu_{j} \cdot g_{j}(x) & =0, \quad j \in J \\
\mu_{j},-g_{j}(x) & \geq 0, \quad j \in J
\end{aligned}
$$

3.2. Parametric programs. We consider nonlinear parametric programs of the form: Let $T \subset \mathbb{R}^{p}$ be some open set. For $t \in T$ find local minimizers $x=x(t)$ of
(7) $P(t): \min _{x \in \mathbb{R}^{n}} f(x, t)$ s.t. $x \in \mathcal{F}(t)$,
where

$$
\mathcal{F}(t):=\left\{x \mid g_{j}(x, t) \leq 0, j \in J\right\} .
$$

For $\bar{t} \in T$ and feasible $\bar{x} \in \mathcal{F}(\bar{t})$ we denote by $J_{0}(\bar{x}, \bar{t})$ the active index set and by $L(x, t, \mu)$ the Lagrangian function

$$
L(x, t, \mu)=f(x, t)+\sum_{j \in J_{0}(\bar{x}, \bar{t})} \mu_{j} g_{j}(x, t) .
$$

To find (near $(\bar{x}, \bar{t})$ ) local minimizers $x$ of $P(t)$ we are looking for solutions $(x, t, \mu)$ of the KKT-equations (with $\mu_{j} \geq 0$ ) (8)

$$
F(x, t, \mu):=\begin{aligned}
\nabla_{x} L(x, t, \mu) & =0 \\
g_{j}(x, t) & =0, j \in J_{0}(\bar{x}, \bar{t}) .
\end{aligned}
$$

From the sufficient optimality conditions in Theorem 5 we obtain

Theorem 6. (Local stability result) Let $\bar{x} \in$ $\mathcal{F}(\bar{t})$. Suppose that with multipliers $\bar{\mu}_{j}$ the KKT condition $\nabla_{x} L(\bar{x}, \bar{t}, \bar{\mu})=0$ is satisfied such that
(1) LICQ holds at $\bar{x}$ wrt. $\mathcal{F}(\bar{t})$.
(2) $\bar{\mu}_{j}>0, \forall j \in J_{0}(\bar{x}, \bar{t})$
and either
(3a) (order one) $\left|J_{0}(\bar{x}, \bar{t})\right|=n$ or
(3b) (order two)

$$
d^{T} \nabla_{x}^{2} L(\bar{x}, \bar{t}, \bar{\mu}) d>0 \forall d \in T_{\bar{x}, \bar{t}} \backslash\{0\}
$$

where $T_{\bar{x}, \bar{t}}$ is the tangentspace $T_{\bar{x}}=$ $\left\{d \mid \nabla_{x} g_{j}(\bar{x}, \bar{t}) d=0, j \in J_{0}(\bar{x}, \bar{t})\right\}$.
(According to Theorem 5, $\bar{x}$ is a local minimizer of $P(\bar{t})$ of order $s=1$ in case (3a) and of order $s=2$ in case (3b)).

Then there exist a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ and $C^{1}$-functions $x: U_{t}(\bar{t}) \rightarrow \mathbb{R}^{n}, \mu$ : $U_{t}(\bar{t}) \rightarrow \mathbb{R}^{\left|J_{0}(\bar{x}, \bar{t})\right|}$ such that $x(\bar{t})=\bar{x}, \mu(\bar{t})=$ $\bar{\mu}$ and for any $t \in U_{t}(\bar{t})$ the point $x(t)$ is a strict local minimizer of $P(t)$ with corresponding multiplier $\mu(t)$. Moreover for $t \in U_{t}(\bar{t})$ the derivatives of $x(t), \mu(t)$ and the value function $v(t)=f(x(t), t)$ are given by

$$
\binom{\nabla x(t)}{\nabla \mu(t)}=-\left[\nabla_{x, \mu} F(x(t), t, \mu(t))\right]^{-1} F(x(t), t, \mu(t))
$$

and

$$
\nabla v(t)=\nabla_{t} L(x(t), t, \mu(t))
$$

Ex. 7 Let $A \in \mathbb{R}^{n \times n}$ be a symmetric matrix and $B \in \mathbb{R}^{n \times m}(n \geq m)$. Suppose the matrix $B$ has full rank $m$ and the following holds:
$d^{T} A d \neq 0 \quad \forall d \in \mathbb{R}^{n}$ such that $B^{T} d=0$. Show that then the following matrix is regular:

$$
\left(\begin{array}{cc}
A & B \\
B^{T} & 0
\end{array}\right)
$$

Rem. Many further (often difficult) results are dealing with the generalization of this stability result under weaker assumptions (i.e., LICQ or SC does not hold; see e.g., [2], [3]).

## 4. LINEAR PARAMETRIC PROGRAMS

4.1. Non-parametric linear programs. Let be given a matrix $A \in \mathbb{R}^{m \times n}$ with $m$ rows $a_{j}^{T}, j \in J:=\{1, \ldots, m\}$ and vectors $b \in \mathbb{R}^{m}, c \in \mathbb{R}^{n}$. We consider primal problems of the form
(9) $\quad P: \max c^{T} x$ s.t. $x \in \mathcal{F}_{P}$

$$
\mathcal{F}_{P}=\left\{x \mid a_{j}^{T} x \leq b_{j}, \quad j \in J\right\}
$$

We often write the feasible set in compact form $\mathcal{F}=\{x \mid A x \leq b\}$. The problem
(10) $\quad D: \min b^{T} y$ s.t. $y \in \mathcal{F}_{D}$

$$
\mathcal{F}_{D}=\left\{y \mid \sum_{j=1}^{m} y_{j} a_{j}=c, y \geq 0\right\}
$$

is called the dual problem. A vector $x \in$ $\mathcal{F}_{P}$ is called feasible for $P$ and a vector $y$ satisfying the feasibility conditions $A^{T} y=$ $c, y \geq 0$ is called feasible for $D$. Let $v_{P}$,
$v_{D}$ resp. denote the maximum value of $P$ resp. minimum value of $D$.

Lemma 1. (weak duality) Let $x$ be feasible for $P$ and $y$ be feasible for $D$. Then

$$
c^{T} x \leq b^{T} y \quad \text { and thus } \quad v_{P} \leq v_{D}
$$

If $c^{T} x=b^{T} y$ holds then $x$ is a maximizer of $P$ and $y$ a minimizer of $D$.

Proof. As Ex.
For $\bar{x} \in \mathcal{F}_{P}$ as usual we define the active index set $J_{0}(\bar{x})=\left\{j \mid a_{j}^{T} x=b_{j}\right\}$. For a subset $J_{0} \subset J$ we denote by $A_{J_{0}}$ the submatrix of $A$ with rows $a_{j}^{T}, j \in J_{0}$ and for $y \in \mathbb{R}^{m}$ by $y_{J_{0}}$ the vector $\left(y_{j}, j \in J_{0}\right)$.
Def. A feasible point $\bar{x} \in \mathcal{F}_{P}$ is called a vertex of the polyhedron $\mathcal{F}_{P}$ if the vectors $a_{j}, j \in J_{0}(\bar{x})$ form a basis of $\mathbb{R}^{n}$ or equivalently if $A_{J_{0}(\bar{x})}$ has rank $n$. (This implies $\left|J_{0}(\bar{x})\right| \geq n$.

The vertex $\bar{x}$ is called nondegenerate if LICQ holds, i.e., $a_{j}, j \in J_{0}(\bar{x})$ are linear independent (implying $\left|J_{0}(\bar{x})\right|=n$ or equivalently $A_{J_{0}(\bar{x})}$ is non-singular).

## Theorem 7.

(a) (Existence and strong duality) If both $P$ and $D$ are feasible then there exist solutions $\bar{x}$ of $P$ and $\bar{y}$ of $D$. Moreover for (any of) these solutions we have

$$
c^{T_{\bar{x}}}=b^{T} \bar{y} \quad \text { and thus } \quad v_{P}=v_{D}
$$

(b) (Optimality conditions) A point $\bar{x} \in$ $\mathcal{F}_{P}$ is a solution of $P$ if and only if there is a corresponding $\bar{y} \in \mathcal{F}_{D}$ such that the complementarity conditions
$\bar{y}^{T}(b-A \bar{x})=0 \quad$ or $\quad \bar{y}_{j}\left(b_{j}-a_{j}^{T} \bar{x}\right)=0, \forall j \in J$
hold or equivalently if there exists $\bar{y}_{j}, j \in$ $J_{0}(\bar{x})$, such that KKT conditions are satisfied:

$$
\sum_{j \in J_{0}(\bar{x})} \bar{y}_{j} a_{j}=c, \quad \bar{y}_{j} \geq 0, j \in J_{0}(\bar{x}) .
$$

It appears that normally the solution of $P$ arises at a vertex of $\mathcal{F}_{P}$.

Lemma 2. If the polyhedron $\mathcal{F}_{P}$ has a vertex (at least one) and $v_{P}<\infty$ then the max value $v_{P}$ of $P$ is also attained at some vertex of $\mathcal{F}_{P}$.

Rem. The Simplex algorithm for solving $P$ proceeds from vertex to vertex of $F_{P}$ until the optimality conditions in Theorem 7(b) are met.
4.2. Parametric linear programs. In a parametric LP we have given a $C^{2}$-matrix function $A(t): \mathbb{R}^{p} \rightarrow \mathbb{R}^{m \times n}$ with $m$ rows $a_{j}^{T}(t), j \in J:=\{1, \ldots, m\}$ and $C^{2}$ vector functions $b(t): \mathbb{R}^{p} \rightarrow \mathbb{R}^{m}, c(t): \mathbb{R}^{p} \rightarrow$ $\mathbb{R}^{n}$ and the open parameter set $T \subset \mathbb{R}^{p}$ : For any $t \in T$ we wish to solve the primal program
(11) $P(t): \max c^{T}(t) x$ s.t. $x \in \mathcal{F}_{P}(t)$

$$
\mathcal{F}_{P}(t)=\{x \mid A(t) x \leq b(t)\}
$$

The corresponding dual reads
(12) $D(t): \min b^{T}(t) y$ s.t. $y \in \mathcal{F}_{D}$

$$
\mathcal{F}_{D}=\left\{y \mid A^{T}(t) y=c(t), y \geq 0\right\}
$$

For $\bar{t} \in T$ and $\bar{x} \in \mathcal{F}_{P}(\bar{t})$ the active index set is $J_{0}(\bar{x}, \bar{t})$.

## Linear Production Model, Shadow Prices

 Assume a factory produces $n$ different products $P_{1}, \ldots, P_{n}$. The production relies on material coming from $m$ different resources $R_{1}, \ldots, R_{m}$ in such a way that the production of 1 unit of a product $P_{j}$ requires $a_{i j}$ units of resource $R_{i}$, for $i=1, \ldots, m$.Suppose we can sell our production for the price of $c_{j}$ per 1 unit of $P_{j}$ and that $b_{i}$ units of each resource $R_{i}$ are available for the total production. How many units $x_{j}$ of each product $P_{j}$ should we produce in order to maximize the total receipt from the sales?

An optimal production plan $\bar{x}=\left(\bar{x}_{1}, \ldots, \bar{x}_{n}\right)^{T}$ corresponds to an optimal solution of the linear program
(13)
$P: \quad \max c^{T} x \quad$ s.t. $A x \leq b, \quad x \geq 0$.

Here $A=\left(a_{i j}\right)$ is the matrix with the elements $a_{i j}$. Let $\bar{x}$ be a solution with corresponding solution $\bar{y}$ of the dual problem (14)
$D: \quad \min b^{T} y \quad$ s.t. $\quad A^{T} \bar{y} \geq c, \bar{y} \geq 0$.
and maximum profit $\bar{z}=c^{T} \bar{x}=b^{T} \bar{y}$.
Could we possibly increase the profit by spending money on increasing the resource capacity $b$ and adjusting the production plan? If so, how much would we be willing to pay for 1 more unit of resource $R_{i}$ ? Let us increase (for fixed $i$ ) the capacity of $R_{i}$ from $b_{i}$ to $b_{i}^{\prime}=b_{i}+t, \bar{y}$ is still feasible. So weak duality gives the following upper bound on the expected profit:

$$
\begin{aligned}
\bar{z}^{\prime} & \leq b_{1} \bar{y}_{1}+\ldots+b_{i}^{\prime} \bar{y}_{i}+\ldots+b_{m} \bar{y}_{m} \\
& =t \cdot \bar{y}_{i}+\sum_{s=1}^{m} b_{s} \bar{y}_{s}=t \cdot \bar{y}_{i}+\bar{z}
\end{aligned}
$$

Accordingly, we would not want to pay more than $t \cdot \bar{y}_{i}$ for $t$ more units of $R_{i}$. In this sense, the coefficients $\bar{y}_{i}$ of the dual optimal solution $\bar{y}$ can be interpreted as the shadow prices of the resources $R_{i}$.
Note that for the value function $v(t)$ in dependence from the parameter $t$ we find

$$
\frac{v(t)-v(0)}{t}=\frac{\bar{z}^{\prime}-\bar{z}}{t} \leq \bar{y}_{i} .
$$

REMARK. The notion of shadow prices furnishes also an intuitive interpretation of complementary slackness. If the slack $\bar{s}_{i}=b_{i}-\sum_{j=1}^{n} a_{i j} \bar{x}_{j}$ is strictly positive at the optimal production $\bar{x}$, we do not use resource $R_{i}$ to its full capacity. Therefore, we would expect no gain from an increase of $R_{i}$ 's capacity.

General case. We come back to the general parametric LP in (11). Suppose for $\bar{t} \in T$ the point $\bar{x} \in \mathcal{F}_{P}(\bar{x})$ is a vertex solution of $P(\bar{t})$. To find for $t$ near $\bar{t}$ solutions $x(t)$ of $P(t)$ we have to find feasible solutions $x$ and $y$ of the system of optimality conditions:

$$
\text { (15) } \quad P: \quad A_{J_{0}(\bar{x}, \bar{t})} x=b_{J_{0}(\bar{x}, \bar{t})}
$$

and
(16)
$D: \quad A_{J_{0}(\bar{x}, \bar{t})}^{T} y_{J_{0}(\bar{x}, \bar{t})}=c_{J_{0}(\bar{x}, \bar{t})}, \quad y_{J_{0}(\bar{x}, \bar{t})} \geq 0$
If $\bar{x}$ is a non-degenerate vertex, i.e., $A_{J_{0}(\bar{x}, \bar{t})}$ is nonsingular, this is possible by applying the IFT to these systems.

Theorem 8. (Local stability result) Let $\bar{x} \in$ $\mathcal{F}_{P}(\bar{t})$ be a vertex solution of $P(\bar{t})$ with corresponding dual solution $\bar{y}_{J_{0}(\bar{x}, \bar{t})}$ such that
(1) $\bar{x}$ is a nondegenerate vertex, i.e., LICQ holds.
(2) $\bar{y}_{j}>0, \forall j \in J_{0}(\bar{x}, \bar{t})$
(SC)
(According to Theorem $5 \bar{x}$ is a local minimizer of $P(\bar{t})$ of order $s=1$.) Then there exist a neighborhood $U_{t}(\bar{t})$ and $C^{1}$-functions $x: U_{t}(\bar{t}) \rightarrow \mathbb{R}^{n}, y_{J_{0}(\bar{x}, \bar{t})}: U_{t}(\bar{t}) \rightarrow \mathbb{R}^{\left|J_{0}(\bar{x}, \bar{t})\right|}$ such that $x(\bar{t})=\bar{x}, y_{J_{0}(\bar{x}, \bar{t})}(\bar{t})=\bar{y}_{J_{0}(\bar{x}, \bar{t})}$ and for any $t \in U_{t}(\bar{t})$ the point $x(t)$ is a vertex solution of $P(t)$ (of order $s=1$ ) with corresponding multiplier $y_{J_{0}(\bar{x}, \bar{t})}(t)$. Moreover for $t \in U_{t}(\bar{t})$ the derivatives of $x(t)$ and the value function $v(t)=c^{T}(t) x(t)$ are given by

$$
\nabla x(t)=\left[A_{J_{0}(\bar{x}, \bar{t})}(t)\right]^{-1}\left(\nabla b_{J_{0}(\bar{x}, \bar{t})}(t)-\nabla A_{J_{0}(\bar{x}, \bar{t})}(t) x\right)
$$

and

$$
\begin{aligned}
& \nabla v(t)=\left[\nabla c_{J_{0}(\bar{x}, \bar{t})}(t)\right]^{T} x \\
& +\left[y_{J_{0}(\bar{x}, \bar{t})}(t)\right]^{T}\left[\nabla b_{J_{0}(\bar{x}, \bar{t})}(t)-\nabla A_{J_{0}(\bar{x}, \bar{t})}^{T}(t) x\right]
\end{aligned}
$$

Rem. The production model case above is a special case where $A, c$ do not depend on $t \in \mathbb{R}$ (so $p=1$ ) and (for fixed $\left.i \in J_{0}(\bar{x}, \bar{t})\right) \frac{1}{d t} b_{J_{0}(\bar{x}, \bar{t})}(t)=e_{i}\left(e_{i}\right.$ is the $i$ th unit vector in $\left.\mathbb{R}^{\left|J_{0}(\bar{x}, \bar{t})\right|}\right)$ the so that

$$
\frac{1}{d t} v(\bar{t})=\left[y_{J_{0}(\bar{x}, \bar{t})}(\bar{t})\right]^{T} e_{i}=\bar{y}_{i} .
$$

## 5. APPLICATIONS

5.1. Interior point methods. The basic idea of the interior point method for solving a non-parametric program
P: $\quad \min _{x \in \mathbb{R}^{n}} f(x) \quad$ s.t. $\quad g_{j}(x) \leq 0, j \in J$ is simply as follows. Consider the perturbed KKT system
(17)
$F(x, \tau, \mu):=$

$$
\begin{aligned}
\nabla f(x)+\sum_{j \in J} \mu_{j} \nabla g_{j}(x) & =0 \\
-\mu_{j} \cdot g_{j}(x) & =\tau, \quad j \in J, \\
\mu_{j},-g_{j}(x) & \geq 0, \quad j \in J .
\end{aligned}
$$

where $\tau>0$ is a perturbation parameter. The idea is to find solutions $x(\tau)$ and $\mu_{j}(\tau)$ of this system (satisfying $-g_{j}(x(\tau)), \mu_{j}(\tau)>$ 0 ) and to let $\tau \downarrow 0$. We expect that $x(\tau)$ converges to a solution $\bar{x}$ of $P$.

Under the sufficient optimality conditions this procedure is well-defined (at least for small $\tau$ ).

Theorem 9. Let $\bar{x}$ be a local minimizer of $P$ such that the sufficient optimality conditions of Theorem 5 are fulfilled with multiplier $\bar{\mu}$ so that $\bar{\mu}_{j}>0$ holds for all $j \in$ $J_{0}(\bar{x})$. Then there exists $C^{1}$-functions $x$ : $(-\alpha, \alpha) \rightarrow \mathbb{R}^{n}, \mu_{j}:(-\alpha, \alpha) \rightarrow \mathbb{R}, j \in$ $J_{0}(\bar{x})(\alpha>0)$ such that $x(0)=\bar{x}, \mu_{j}(0)=$ $\bar{\mu}_{j}$, and $x(\tau), \mu_{j}(\tau)$ are locally unique solutions of (17)

Proof. Follows by applying the IFT to the equation (17).
5.2. A parametric location problem. We consider a concrete location problem in Germany (see [6] for details). Suppose some good is produced at 5 existing plants at location $s^{j}=\left(s_{1}^{j}, s_{2}^{j}\right), j=1, \ldots, 5\left(s_{1}^{j}\right.$ longitude, $s_{2}^{j}$ latitude in Germany) and a sixth new plant has to be build at location $t=\left(t_{1}, t_{2}\right)$ (to be determined) to satisfy the demands of $V_{i}$ units of goods in 99 towns $i$ at location $\ell^{i}=\left(\ell_{1}^{i}, \ell_{2}^{i}\right), i=$ $1, \ldots, 99$. Suppose (for simplicity) that the transportation cost $c_{i j}$ from plant $j$ to town $i$ (per unit of the good) is (proportionally to) the Euclidian distance

$$
\begin{gathered}
c_{i j}=\sqrt{\left(s_{1}^{j}-\ell_{1}^{i}\right)^{2}+\left(s_{2}^{j}-\ell_{2}^{i}\right)^{2}}, j=1, . ., 5, \\
c_{i 6}(t)=\sqrt{\left(t_{1}-\ell_{1}^{i}\right)^{2}+\left(t_{2}-\ell_{2}^{i}\right)^{2}}, \quad \forall i .
\end{gathered}
$$

Suppose further that the total demand $V=$
$\sum_{i} V_{i}$ will be produced in the 6 plants with
a production of $p_{j}$ units of the good in plant $j$ where
$p_{1}=V \frac{10}{100}, p_{2}=V \frac{30}{100}, p_{3}=V \frac{10}{100}$,
$p_{4}=V \frac{15}{100},=p_{5}=V \frac{15}{100}, p_{6}=V \frac{20}{100}$.
The problem now is to find the location $t=\left(t_{1}, t_{2}\right)$ of the new plant such that the total transportation costs are minimized. For any fixed location $t$ the optimal transportation strategy is given by the solution of the transportation problem (standard LP),

$$
\begin{aligned}
P(t)::= & \min _{y_{i j}} \sum_{j=1}^{5} \sum_{i} c_{i j} y_{i j}+\sum_{i} c_{i 6}(t) y_{i 6} \quad \text { s.t. } \\
& \sum_{i} y_{i j}=p_{j}, \quad j=1, \ldots, 6, \\
& \sum_{j} y_{i j}=V_{i}, \quad i=1, \ldots, 99 .
\end{aligned}
$$

Here $y_{i j}$ is the number of units of the good to be transported from plant $j$ to town $i$. The problem is now to find a (global or local) minimizer of $v(t)$. Most local minimization algorithm are based on the computation of the (negative) gradient of the objective function at some actual point $t=$ $t^{k}, d=-\nabla v\left(t^{k}\right)$.
Suppose that $y_{i j}^{k}$ is the vertex solution of $P\left(t^{k}\right)$. Then by the results of Section 4.2 the gradient can be computed via the formola

$$
\nabla v\left(t^{k}\right)=\nabla_{t} L\left(y^{k}, t^{k}, \lambda^{k}\right)=
$$

$\sum_{i=1}^{99} y_{i 6}^{k} \frac{1}{\sqrt{\left(t_{1}-\ell_{1}^{i}\right)^{2}+\left(t_{2}-\ell_{2}^{i}\right)^{2}}}\binom{\left(t_{1}-\ell_{1}^{i}\right)}{\left(t_{2}-\ell_{2}^{i}\right)}$

## 6. Pathfollowing in practice

We shortly discuss how a solution curve ( $x(t), t$ ) of a one-parametric equation $F(x, t)=0 \quad F: \mathbb{R}^{n} \times \mathbb{R} \rightarrow \mathbb{R}^{n}, t \in \mathbb{R}$, can be followed numerically.
The basic idea is to use some sort of Newton procedure. Recall that the classical Newton method is the most fundamental approach for solving a system of $n$ equations in $n$ unknowns:

$$
F(x)=0 \quad F: \mathbb{R}^{n} \rightarrow \mathbb{R}^{n}
$$

The famous Newton iteration for computing a solution is to start with some (appropriate) starting point $x^{0}$ and to iterate according to
$x^{k+1}=x^{k}-\left[\nabla F\left(x^{k}\right)\right]^{-1} F\left(x^{k}\right), \quad k=0,1, \ldots$
It is well-known that this iteration converges quadratically to a solution $\bar{x}$ of $F(\bar{x})=$ 0 if

- $x^{0}$ is chosen close enough to $\bar{x}$ and if
- $\nabla F(\bar{x})$ is a non-singular matrix.

The simplest way to follow approximately a solution curve $x(t)$ of $F(x, t)=0$, i.e., $F(x(t), t)=0$, on an interval $t \in[a, b]$ is to discretize $[a, b]$ by

$$
t_{\ell}=a+\ell \frac{b-a}{N}, \quad \ell=0, \ldots, N
$$

(for some $N \in \mathbb{N}$ ) and to compute for any $\ell=0, \ldots, N$, a solution $x_{\ell}=x\left(t_{\ell}\right)$ of $F\left(x, t_{\ell}\right)=0$ by a Newton iteration, $x_{\ell}^{k+1}=x_{\ell}^{k}-\left[\nabla F\left(x_{\ell}^{k}, t_{\ell}\right)\right]^{-1} F\left(x_{\ell}^{k}, t_{\ell}\right), \quad k=0,1,$. starting with $x_{\ell}^{0}=x_{\ell-1}($ for $\ell \geq 1)$.
We refer the reader to the book [1] for details e.g., on:

- How to perform pathfollowing efficiently?
- How to deal with branching points $(\bar{x}, \bar{t})$ where different solution curves intersect?


## 7. General parametric PROGRAMMING

In the next sections we analyze the parametric behavior under weaker assumptions where the Implicit Function Theorem is no more applicable. We try to keep the introduction of 'new' concepts to a minimum and to motivate the results by examples.

Consider again the parametric optimization problem
(18) $P(t): \min _{x \in \mathbb{R}^{n}} f(x, t)$ s.t. $x \in F(t)$
$F(t):=\left\{x \in \mathbb{R}^{n} \mid g_{j}(x, t) \leq 0, j \in J\right\}$,
depending on the parameter $t \in T$, where $T \subset \mathbb{R}^{p}$ is an open parameter set. Again $J:=\{1, \ldots, m\}$. All functions $f, g_{j}$ are assumed to be (at least) continuous everywhere.

Notation: Let $v(t)=\min _{x \in \mathcal{F}(t)} f(x, t)$ denote the minimal value of $P(t)(v(t)=$ $\infty$ if $F(t)=\emptyset)$ and let $S(t)$ the set of (global) minimizers. The mappings $F$ : $T \rightrightarrows \mathbb{R}^{n}$ and $S: T \rightrightarrows \mathbb{R}^{n}$ are so-called setvalued mappings.
Problem of parametric optimization: How do the value function $v(t)$ and the mappings $F(t), S(t)$ change with $t$. (Continuously, smoothly?)

Definition 1. Let $v: T \rightarrow \mathbb{R}_{\infty}$ be given, $\mathbb{R}_{\infty}=\mathbb{R} \cup\{-\infty, \infty\}$.
(a) The function $v$ is called upper semicontinuous (usc) at $\bar{t} \in T$ if for any $\varepsilon>0$ there exists $\delta>0$ such that

$$
v(t) \leq v(\bar{t})+\varepsilon \quad \text { for all }\|t-\bar{t}\|<\delta .
$$

(b) The function $v$ is called lower semicontinuous (lsc) at $\bar{t} \in T$ if for any $\varepsilon>0$
there exists $\delta>0$ such that

$$
v(t) \geq v(\bar{t})-\varepsilon \quad \text { for all }\|t-\bar{t}\|<\delta .
$$

We shall see that the lower- and upper semicontinuity of the value function $v(t)$ depend on different assumptions. Obviously to assure the lower semicontinuity of $v$ at $\bar{t}$ the feasible set $F(t)$ should not become essentially larger by a small perturbation $t$ of $\bar{t}$ and to assure the upper semicontinuity of $v$ the set $F(t)$ should not become essentially smaller after a perturbation. To avoid an 'explosion' of $F(t)$ we will need some compactness assumptions for $F(t)$ and to prevent an 'implosion' a Constraint Qualification will be needed.

## Definition 2. Let the set valued mapping

 $F: T \rightrightarrows \mathbb{R}^{n}$ be given.(a) $F$ is called closed at $\bar{t} \in T$ if for any sequences $t_{l}, x_{l}, l \in \mathbb{N}$, with $t_{l} \rightarrow \bar{t}, x_{l} \in$ $F\left(t_{l}\right)$ the condition $x_{l} \rightarrow \bar{x}$ implies $\bar{x} \in$ $F(\bar{t})$.
(b) (no explosion of $F(t)$ after perturbation of $t=\bar{t}) \quad F$ is called outer semicontinuous (osc) at $\bar{t} \in T$ if for any sequences $t_{l}, x_{l}, l \in \mathbb{N}$ with $t_{l} \rightarrow \bar{t}, x_{l} \in F\left(t_{l}\right)$ there exists $\bar{x}_{l} \in F(\bar{t})$ such that $\left\|x_{l}-\bar{x}_{l}\right\| \rightarrow 0$ for $l \rightarrow \infty$.
(c) (no implosion of $F(t)$ after perturbation of $t=\bar{t}) \quad F$ is inner semicontinuous (isc) at $\bar{t} \in T$ if for any $\bar{x} \in F(\bar{t})$ and sequence $t_{l} \rightarrow \bar{t}$ there exists a sequence $x_{l}$ such that $x_{l} \in F\left(t_{l}\right)$, for $l$ large enough, and $\left\|x_{l}-\bar{x}\right\| \rightarrow 0$.

The mapping $F$ is called continuous at $\bar{t}$ if it is both osc and isc at $\bar{t}$

Ex. 8 Show for $F(t)=\left\{x \in \mathbb{R}^{n} \mid g_{j}(x, t) \leq\right.$ $0, j \in J\}, t \in T$ ( $g_{j}$ continuous) that the mapping $F: T \rightrightarrows \mathbb{R}^{n}$ is closed on $T$.
Lower semicontinuity of $v(t)$. To assure lower semicontinuity of $v$ at $\bar{t}$ we (minimally) need compactness of $F(\bar{t})$ (even in the case that $F(t)$ behaves continuously). Ex. 9 (Linear problem, $F(t) \equiv F$ constant not bounded and $v$ is not lsc.) For the problem $\min x_{2}-t x_{1}$ s.t. $x_{1} \geq 0, x_{2} \geq 0$ we find

$$
\begin{gathered}
v(t)=\left\{\begin{array}{cc}
0 \quad \text { for } t \leq 0 \\
-\infty \text { for } t>0
\end{array}\right. \\
S(t)=\left\{\begin{array}{cc}
\{(0,0)\} & \text { for } t<0 \\
\left\{\left(x_{1}, 0\right) \mid x_{1} \geq 0\right\} & \text { for } t=0 \\
\emptyset & \text { for } t>0
\end{array}\right.
\end{gathered}
$$

We even need the following stronger condition

LC. (local compactness of $F$ at $\bar{t}$ ) There exists $\varepsilon>0$ and a compact set $C_{0}$ such that

$$
\bigcup_{\|t-\bar{t}\| \leq \varepsilon} F(t) \subset C_{0} .
$$

Without this condition LC the lower semicontinuity of $v$ is not assured in general. Ex. $10(F(\bar{t}), S(\bar{t})$ compact, LC does not hold and $v$ is not lsc and $F(t)$ is not ose at $\bar{t}$.) Consider the problem

$$
\begin{gathered}
\min x_{2}-x_{1} \quad \text { s.t. } \quad x_{2} \leq 2 t x_{1}-\frac{1}{2} \\
x_{2} \leq-t x_{1}, \quad x_{2} \geq x_{1}(t)
\end{gathered}
$$

with a function $x_{1}(t), x_{1}(0)=-1, x_{1}(t)=$ $-\frac{1}{4}$ for $|t| \geq 2$ (sketch the problem as an Ex.) we find with continuous functions
$v_{l}(t), x(t):$

$$
v(t)=\left\{\begin{aligned}
v_{l}(t) & \text { for } t \leq 0 \\
-\frac{1}{2}-\sqrt{\ln (2)} & \text { for } t=0 \\
-\frac{1}{4}\left(1+\frac{1}{t}\right) & \text { for } t>0
\end{aligned} \quad\right. \text { and }
$$

$$
S(t)=\left\{\begin{array}{cc}
\{(x(t)\} & \text { for } t \leq 0 \\
\left\{\frac{1}{4}\left(\frac{1}{t},-1\right)\right\} & \text { for } t>0
\end{array}\right.
$$

The lower semicontinuity of $v$ depends on the following technical outer semicontinuity and compactness condition saying that for $t$ near $\bar{t}$ at least one point $x_{t} \in S(t)$ can be approached by elements in a compact subset of $F(\bar{t})$.
AL. There exists a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ and a compact set $\bar{C} \subset \mathbb{R}^{n}$ such that for all $t \in U_{t}(\bar{t})$ with $F(t) \neq \emptyset$ there is some $x_{t} \in S(t)$ and some $\bar{x}_{t} \in F(\bar{t}) \cap \bar{C}$ satisfying $\left\|x_{t}-\bar{x}_{t}\right\| \rightarrow 0$ for $t \rightarrow \bar{t}$.

## Lemma 3.

(a) Let AL be satisfied at $\bar{t}$. Then $v$ is lsc at $\bar{t}$.
(b) Let the local compactness condition $L C$ be fulfilled at $\bar{t}$. Then $A L$ is satisfied ( i.e., $v$ is lsc at $\bar{t}$ ).

Ex. 11 Let the local compactness condition LC be fulfilled at $\bar{t}$ then the mapping $F$ is osc at $\bar{t}$.

The convex case. By Ex. 10 in the general (non-convex) case the condition $\emptyset \neq$ $F(\bar{t})$ compact is not sufficient to assure the outer semicontinuity of $F$ and the condition $\emptyset \neq S(\bar{t})$ compact does not imply the lower semicontinuity of $v$. Under the following convexity assumptions the situation is changed.

Recall that a function $f(x), f: \mathbb{R}^{n} \rightarrow \mathbb{R}$ is called convex if for any $x_{1}, x_{2} \in \mathbb{R}^{n}$ and $\tau \in[0,1]$ it follows
$f\left((1-\tau) x_{1}+\tau x_{2}\right) \leq(1-\tau) f\left(x_{1}\right)+\tau f\left(x_{2}\right)$.

AC. For each (fixed) $t \in T$ the functions $g_{j}(x, t)$ are convex in $x$ for all $j \in J$.
$\mathbf{A C}_{0}$. In addition to AC , for each (fixed) $t \in T$ the function $f(x, t)$ is convex in $x$, (i.e., the problems $P(t)$ are convex programs).

Lemma 4. Let the convexity condition $A C$ hold and assume $\emptyset \neq F(\bar{t})$ is bounded (compact). Then the local compactness condition LC is satisfied. In particular $F$ is osc (cf. Ex.11) and v is lsc at $\bar{t}$ (cf. Lemma 3). In the convex case even the boundedness of $S(\bar{t})$ is sufficient to assure that $v$ is lsc at $\bar{t}$.

Theorem 10. Let the convexity assumption $A C_{0}$ hold and let $S(\bar{t})$ be nonempty and bounded (compact). Then $v$ is lsc at $\bar{t}$.

The upper semicontinuity of $v(t)$. The upper semicontinuity of $v$ depends on a different assumption. The local compactness condition LC is not sufficient (and not necessary).
Ex. 12 For the problem
$\min x_{1}$ s.t. $x_{1}^{2}+x_{2}^{2} \leq-t$, which obviously satisfies LC we find

$$
F(t)=\left\{\begin{array}{cc}
\left\{x_{1}^{2}+x_{2}^{2} \leq|t|\right\} & \text { for } t<0 \\
\{(0,0)\} & \text { for } t=0 \\
\emptyset & \text { for } t>0
\end{array} \quad\right. \text { and }
$$

$$
v(t)=\left\{\begin{array}{c}
t \text { for } t \leq 0 \\
\infty \text { for } t>0
\end{array}\right.
$$

The problem here is that the mapping $F$ is not isc at $\bar{t}$. To assure the upper semicontinuity of $v$ at $\bar{t}$ we only need an inner semicontinuity condition at one point $\bar{x} \in S(\bar{t})$.
AU. There exist a minimizer $\bar{x} \in S(\bar{t})$ and a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ such that for all $t \in U_{t}(\bar{t})$ there is some $x_{t} \in F(t)$ satisfying $\left\|x_{t}-\bar{x}\right\| \rightarrow 0$ for $t \rightarrow \bar{t}$.

Lemma 5. Let $A U$ be fulfilled at $\bar{t}$. Then $v$ is usc at $\bar{t}$.

A natural condition to force the assumption AU is a so-called Constraint Qualification (CQ).

Definition 3. The Constraint Qualification CQ is said to hold at $(\bar{x}, \bar{t})$ with $\bar{x} \in F(\bar{t})$ if there is a sequence $x_{v} \rightarrow \bar{x}$ such that

$$
g_{j}\left(x_{\nu}, \bar{t}\right)<0 \quad \text { holds for all } j \in J
$$

# Corollary 1. Let CQ be satisfied at $(\bar{x}, \bar{t})$ 

 for (at least) one point $\bar{x} \in S(\bar{t})$. Then the condition $A U$ is satisfied, i.e., $v$ is usc at $\bar{t}$.Ex. 13 Let CQ hold at $(\bar{x}, \bar{t}), \bar{x} \in F(\bar{t})$. Then there is a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ such that $F(t)$ is nonempty for all $t \in U_{t}(\bar{t})$. If CQ holds at $(x, \bar{t})$ for each point $x \in$ $F(\bar{t})$ then $F$ is isc at $\bar{t}$.

The behavior of $\boldsymbol{S}(\boldsymbol{t})$. Let us shortly study the continuity properties of the mapping $S(t)$.
Obviously the inner semicontinuity of $S$ is stronger than the condition AU. So if $S$ is isc the function $v$ is usc (see Lemma 5). However the inner semicontinuity of $S(t)$ is a very 'strong' condition. Even if the local compactness condition LC and the Constraint Qualification hold it need not
to be satisfied. We give an example.
Ex. 14 (LC and CQ holds but $S$ is not isc.) $\min x_{2}-t x_{1}$ s.t. $\left|x_{1}\right| \leq 1,\left|x_{2}\right| \leq 1$. Then near $\bar{t}=0$ we obtain

$$
S(t)=\left\{\begin{array}{cc}
\{(-1,-1)\} & \text { for } t<0 \\
\left\{\left(x_{1},-1\right)| | x_{1} \mid \leq 1\right\} & \text { for } t=0 \\
\{(1,-1)\} & \text { for } t>0 \\
v(t)=-1-|t| . & \text { and }
\end{array}\right.
$$

We now discuss the closedness and the outer semicontinuity of $S$.
Ex. 15 Let CQ be satisfied at $(\bar{x}, \bar{t})$ for (at least) one point $\bar{x} \in S(\bar{t})$. Then $S$ is closed at $\bar{t}$
Ex. 16 Let $S(\bar{t})$ be compact and assume $\emptyset \neq S(t)$ for a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ and $S$ is osc at $\bar{t}$. Then AL holds implying that $v$ is lsc at $\bar{t}$ (see Lemma 3).

## Lemma 6. Let LC be satisfied at $\bar{t}$ and let CQ hold at $(\bar{x}, \bar{t})$ for (at least) one $\bar{x} \in$ $S(\bar{t})$. Then there exists a neighborhood $U_{t}(\bar{t})$ of $\bar{t}$ such that for all $t \in U_{t}(\bar{t})$ the set $S(t)$ is nonempty and compact. Moreover the mapping $S$ is osc at $\bar{t}$.

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