

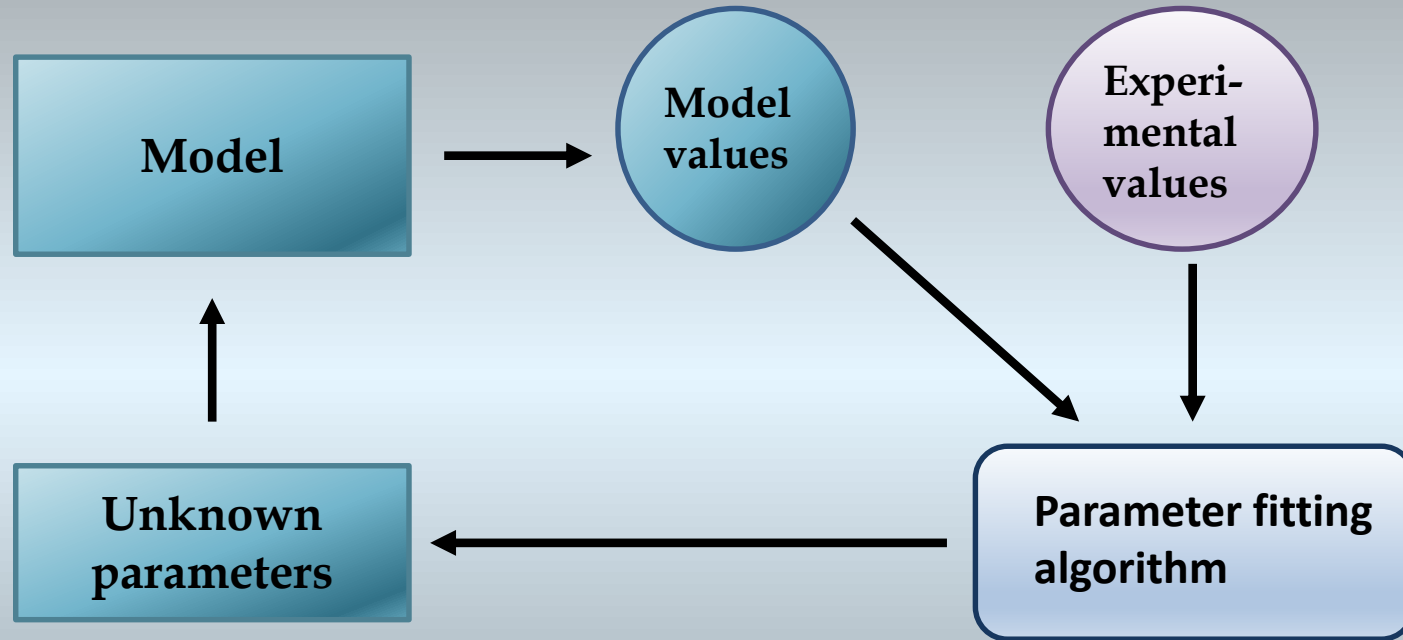
# Parameter estimation : introduction

When starting a modeling project usually many parameters of the model are not known

How can I find out about parameter values?

- experimental approach: try to design an experiment for measuring the specific parameter
  - typically *in vitro* experiment (e.g. for rate constants: put different amounts of substrate in a test tube and measure how fast the reaction proceeds)
  - Problems: often not possible, too many parameters
- Systems biology approach: adapt a complete model to experimental data

## Parameter estimation : basic idea of parameter fitting



Change the parameter values of a model in order to that it best fits the experimental data

# Parameter estimation : basic idea of parameter fitting

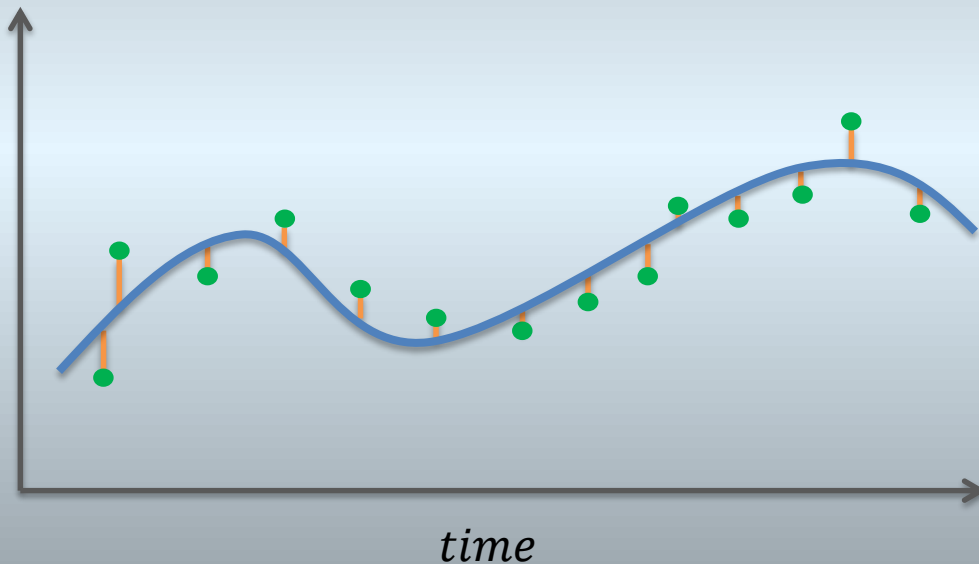
How to determine the “best” fit for a given set of experimental data ?

We will use heuristics

- Computation of the probability that the measurements (experimental data) would be the results of a simulation of the model
- A high probability means that the model is good
- Criterion: likelihood is maximal when the difference between measurement and simulation results is minimal (easy to calculate)

# Parameter estimation

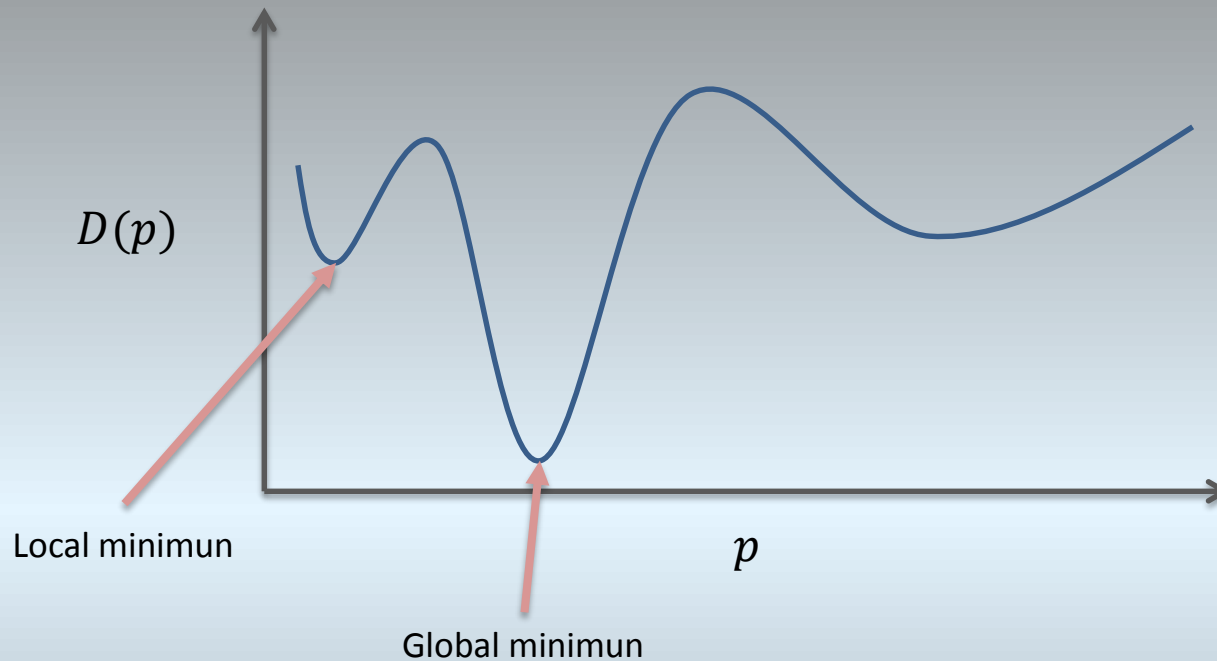
The parameters inference problem for ordinary differential equation models is usually formulated as an optimization problem with an objective function that has to be minimized by adjusting the values of the model parameters. A common choice to compute this objective function is to calculate the sum of squared errors between measurements and model predictions : the least squares distance measure



$$D(p) = \sum_{i=1}^N (x_i - y_i(p))^2$$

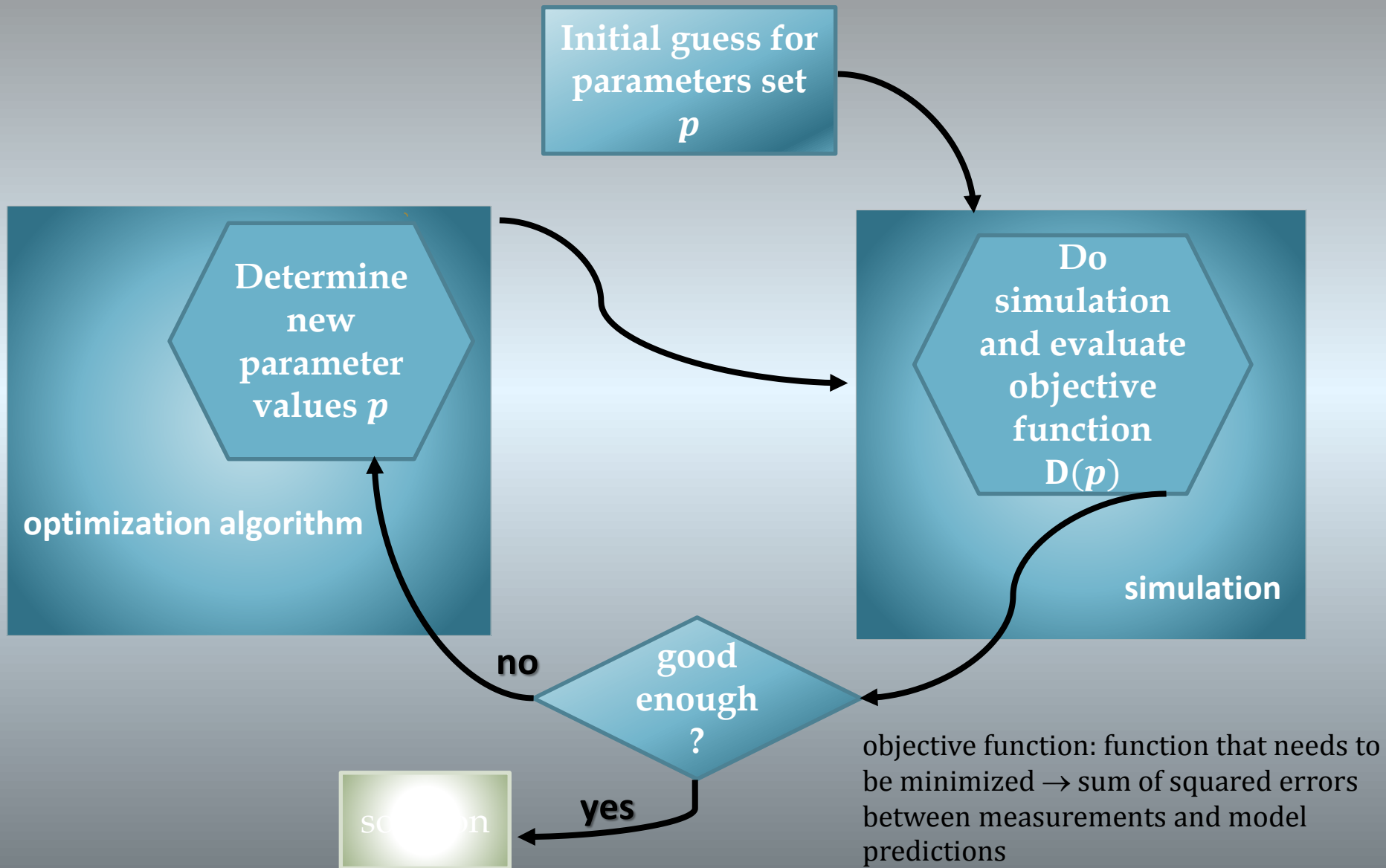
A compound is tracked over time and we obtained  $N$  values. Thus  $N$  is the number of data point,  $x_i$  is the measured value for time  $t_i$  and  $y_i(p)$  is the simulated value for time  $t_i$  for a set of parameter values  $p$

## Parameter estimation : parameter space



- The objective function may have many local minima
- If we have  $N$  parameters to estimate, the parameters represent an  $N$ -dimensional space, the parameter space
- A specific solution (specific parameter values) will correspond to a point in the parameter space
- We need a way to find the set of parameter values (a point in parameter space) for which the distance  $D$  is minimal (the best fit)
- We will use an optimization algorithm since a systematic scan of the parameter space is not possible when the space dimension is large

# Parameter estimation : numerical optimization cycle



# Parameter estimation : optimization algorithm

Different methods have been proposed:

Local optimization methods tend to converge quickly but have a tendency to get stuck in local optima

Global methods might take time but ensure the global optimum

Focus on the **particle swarm optimization (PSO)** method since its performance compared to the fourth most popular optimization methods (Evolutionary Computation, Evolutionary Programming, Genetic Algorithms and Simulated Annealing) reveals that the PSO method performs the best in systems biology (Baker *et al*, 2010, Journal of Integrative Bioinformatics, 7(3):133).

PSO belongs to the class of stochastic global optimization methods which depend on probabilistic approaches.

PSO (optimization par essais particuliers) was first proposed by Kennedy and Eberhart (1995, In *Proceedings of the Sixth International Symposium on Micro Machine and Human Science MHS95, IEEE Press*, 3943). It is inspired by social behavior and movement dynamics of insects, birds and fishes.

# Parameter estimation : particle swarm optimization method

The swarm is typically modeled by particles that have a position and a velocity in multidimensional space. These particles roam through the hyperspace and have two essential reasoning capabilities: A particle is described by a **position vector** in the parameter space and a **velocity vector**. The velocity of a particle represents the direction of its parameter space exploration and the speed of the movement.

Each particle possesses:

- the memory of its own previous experience and remembers its best achievement (*pbest*)
- Information about the best solution attained within its neighbors . The “global” version of the optimizer keeps track of the overall best value, and its location, obtained thus far by any particle in the population (*gbest*). In the “local” version, each particle keeps track of the best solution attained within a *local* topological neighborhood of particles (*lbest*)

Each particle of the swarm is randomly initialized for its position and velocity. These particles roam through the parameter space and optimization concept consists of, at each time step, changing the velocity (accelerating) of each particle toward its *pbest* and *gbest* or *lbest*.

Here, a particle will correspond to the set of kinetic parameters that have to be estimated and a best achievement corresponds to the smallest value obtained for the objective function



# Parameter estimation : particle swarm optimization method

Let  $S$  be the number of particles in the swarm.

Each particle  $i$  has a position  $\mathbf{x}_i \in \mathbb{R}^n$  in the search-space and a velocity  $\mathbf{v}_i \in \mathbb{R}^n$

Let  $\mathbf{p}_i$  the best known position of particle  $i$  and  $\mathbf{n}_i$  the best known position of its neighbor

Let  $f$  the objective function which must be minimized

## Initialization

for each particle  $i = 1, \dots, S$  do

Initialize randomly the particle position vector  $\mathbf{x}_i$

Initialize the particle's best position  $\mathbf{p}_i$  with  $\mathbf{x}_i$  ( $\mathbf{p}_i \leftarrow \mathbf{x}_i$ )

If  $f(\mathbf{p}_i) < f(\mathbf{n}_i)$  then

Update the neighbor's best position  $\mathbf{n}_i \leftarrow \mathbf{p}_i$

Initialize the particle velocity

## While a termination criterion is not reached do

for each particle  $i = 1, \dots, S$  do

Update the particle velocity as follow:

$$\mathbf{v}_i = w \mathbf{v}_i + c_1 r_1 (\mathbf{p}_i - \mathbf{x}_i) + c_2 r_2 (\mathbf{n}_i - \mathbf{x}_i)$$

Update the particle position:

$$\mathbf{x}_i = \mathbf{x}_i + \mathbf{v}_i$$

If  $f(\mathbf{x}_i) < f(\mathbf{p}_i)$  then

Update the particle best known position  $\mathbf{p}_i \leftarrow \mathbf{x}_i$

If  $f(\mathbf{p}_i) < f(\mathbf{n}_i)$  then

Update the neighbor's best position  $\mathbf{n}_i \leftarrow \mathbf{p}_i$

## termination criterion:

the specified number of iteration or the value of the objective function is  $<$  than a given threshold and a solution has been found

$w$  = inertia

$r_1$  and  $r_2$  = random number

In general  $c_1 = c_2 = 2$

# Parameter estimation : particle swarm optimization method

Each iteration in PSO execution, requires for each particle of the swarm:

1. the values of the position vectors are set as the values of the model parameters
2. the model is simulated, by numerical integration of the ODE system, to produce the dynamic profiles corresponding to those parameter values
3. the simulated data are compared to the experimental data using the objective function described above

The iterative process will stop if the change of the objective function value is smaller than a specified value or if the number of specified iterations is reached.

# Parameter estimation

Important:

- The result of a parameter fitting always needs to be inspected afterwards
- Having a good result for a fit does **not** mean that the parameter value is the „true“ one. This depends on the assumptions about the errors and the correctness of the model.
- For the stochastic algorithms the result is not reproducible

# Parameter estimation in COPASI

The screenshot shows the COPASI 4.5 interface with the 'Parameter Estimation' dialog box open. The dialog is titled 'fitting - COPASI 4.5 (Build 30) Users/.../presentations/fitting.cps'. The left sidebar shows the 'Copasi' tree with 'Parameter Estimation' selected. The main window displays a list of parameters to be estimated, their bounds, start values, and affected experiments. The 'Method' is set to 'Particle Swarm' with various parameters like 'Iteration Limit' and 'Swarm Size'.

Model

select parameter estimation

choose optimization algorithm

list of unknown parameters (including ranges)

Choose experimental data (possible several experiments)

update model

executable

Experimental Data

Parameters (6) Constraints (0)

ID	Parameter Definition
1	$0.0001 \leq (R1).k1 \leq 10$ ; Start Value = 1
2	$0.0001 \leq (R2).v$ ; {Experiment} $\leq 10$ ; Start Value = 0.12
3	$0.0001 \leq (R2).v$ ; {Experiment_1} $\leq 10$ ; Start Value = 0.12
4	$0.0001 \leq (R3).v \leq 10$ ; Start Value = 0.12
5	$0.0001 \leq (R4).Km \leq 10$ ; Start Value = 0.1

Object: (R1).k1

Lower Bound:  - Infinity 0.0001

Upper Bound:  + Infinity 10

Start Value: 1

Affected Experiments:  all

Duplicate for each Experiment

Method: Particle Swarm

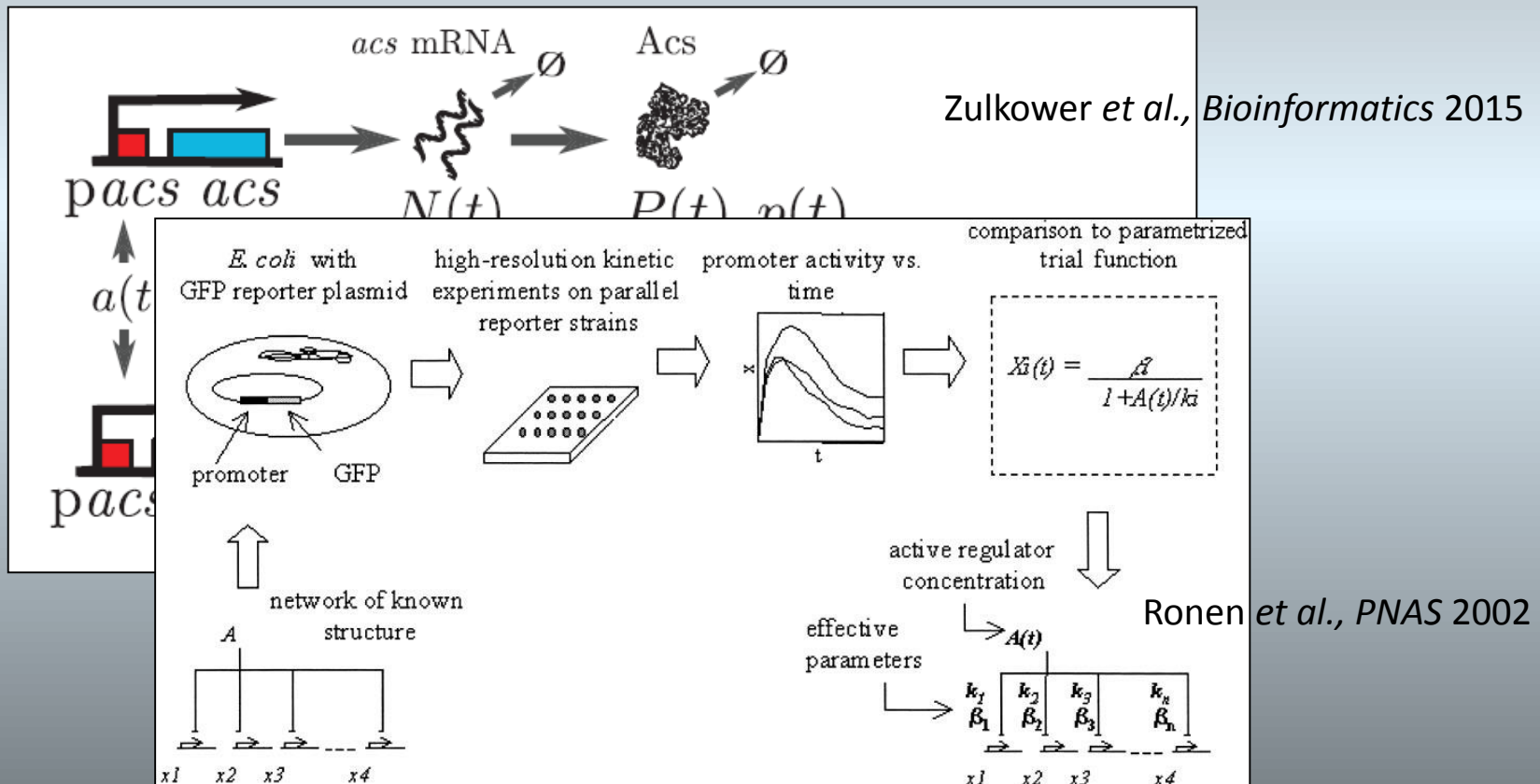
Method Parameter	Value
Iteration Limit	2000
Swarm Size	50
Std. Deviation	1e-06
Random Number Generator	1

Run Revert Report Output Assistant

# Experimental data

**Example of experimental time-series data:** transcriptional fusion of a fluorescence (GFP) or luminescence (luciferase) reporter gene to the promoters of the target genes

Measurement techniques allow real-time and in-vivo monitoring of gene expression



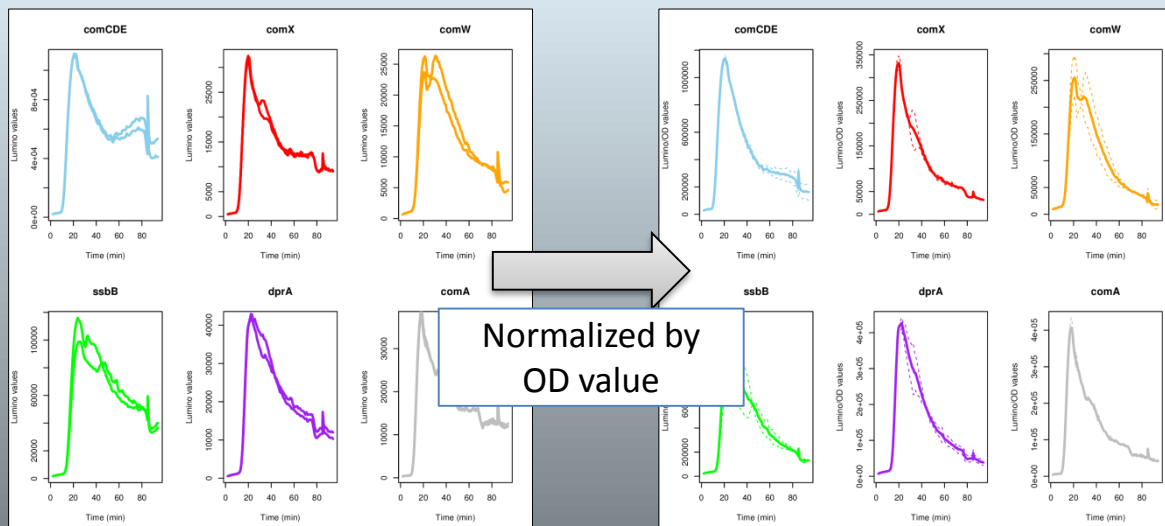
# Normalization of luminescence data

The quantity of luminescence per cell as a function of time ( $r(t)$ ) is :  $r(t) = \frac{I(t)}{A(t)}$  with

- $I(t)$  is the luminescence intensity (in RLU)
- $A(t)$  the absorbance values corrected by subtraction of the absorbance background measured on wells containing only growth medium

Since the luciferase does not require any post-translational modification such as folding, this ratio estimates the average concentration of reporter protein per cell.

The dynamics of the system is conveniently described by the temporal evolution of the luciferase concentration.



## Use of the green fluorescent reporter gene



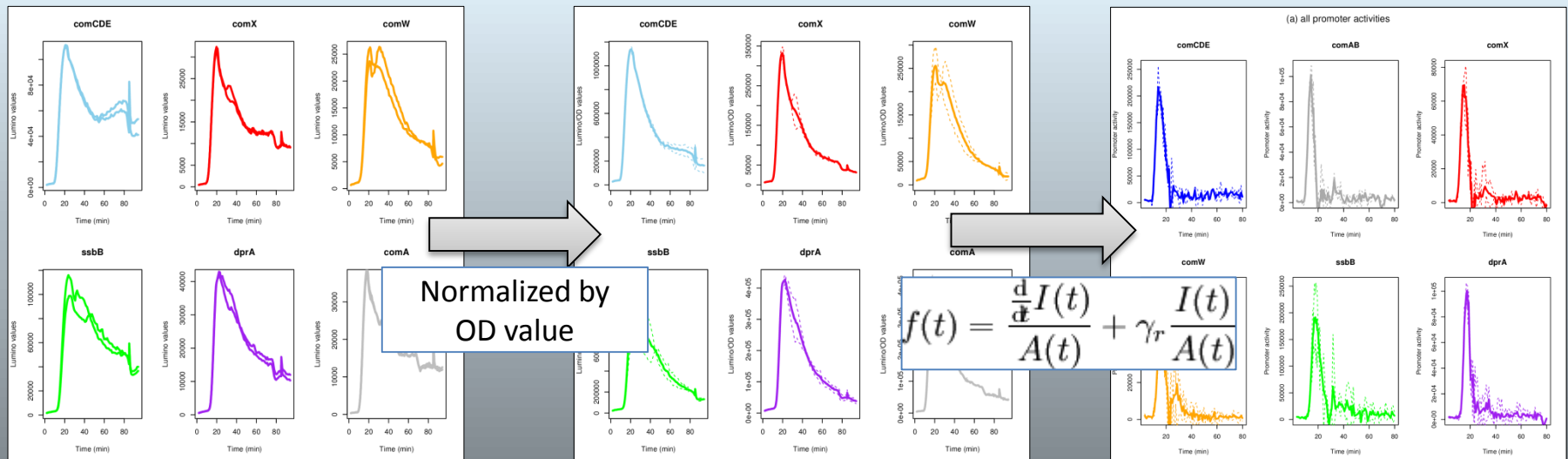
- Fluorescent activity of GFP in response to light excitation depends on post-translational modifications, notably the folding of the protein to an appropriate conformation, including the autocatalytic formation of the chromophore.
- This maturation process gives rise to an additional reaction step from GFP to active GFP.
- See de Jong *et al. BMC Systems Biology* 2010, **4**:55 for correct normalization of fluorescence signal

# Promoter activities deduced from luminescence signal

Promoter activities are deduced using its derivative according to the following formula (Stefan *et al*, 2015, *PLoS Comput. Biol.* **11** e1004028):

$$f(t) = \frac{d}{dt}r(t) + (\gamma_r + \mu(t))r(t) = \frac{d(I(t))}{A(t)} + \gamma_r \frac{I(t)}{A(t)}$$

where  $\gamma_r$  [ $\text{min}^{-1}$ ] is the degradation constant of the luciferase protein and  $\mu(t)$  [ $\text{min}^{-1}$ ] is the growth rate of the bacteria





# protein concentration kinetics

Computation of the concentration evolution of the protein of interest over time:

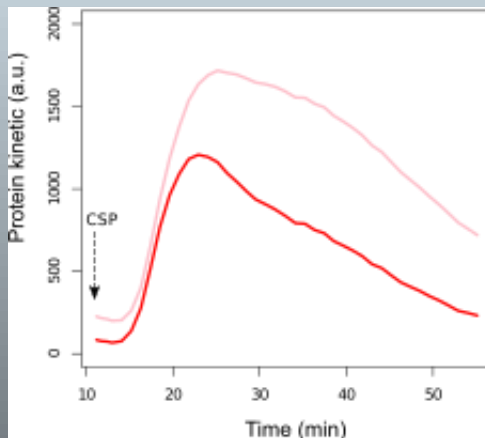
→ Correction to take into account the differences in half-lives between the reporter luciferase and the protein whose gene activity is measured (Stefan *et al*, 2015, *PLoS Comput. Biol.* **11** e1004028):

$$\frac{d}{dt}p(t) = f(t) - (\gamma_p + \mu(t))p(t), \quad p(0) = p_0 = \frac{\mu(T) + \gamma_r}{\mu(T) + \gamma_p} r(T)$$

where  $\gamma_p$  [ $\text{min}^{-1}$ ] is the degradation constant of the protein and  $\mu(T)$  is the growth rate of bacteria at the end of the preculture procedure (at time T)

Correction effects:

- protein of interest with a shorter life times than luciferase: the uncorrected values clearly overestimate the protein concentration (red curves)
- protein of interest with a higher life times than luciferase: the uncorrected values underestimate the protein concentration (blue curves)



- Dark color lines protein concentration kinetics taking into account only protein life time
- Light color lines protein kinetics after correction

