

# Kinetic parameter estimation in biochemical reaction networks using observability extensions



Hamilton Institute  
National University Ireland Maynooth

Dirk Fey<sup>1,2</sup> and Eric Bullinger<sup>1,2</sup>

<sup>1</sup>Hamilton Institute, National University Ireland, Maynooth, IRL  
<sup>2</sup>Industrial Control Centre, University of Strathclyde, Glasgow, UK



University of  
**Strathclyde**  
Glasgow

## Introduction

Accurate & reliable **parameter estimation** [1]

- Vital part of mathematical modeling
- Bottleneck in systems biology
- Becoming feasible (better measurements)

## Problem statement

**Kinetic reaction model** (ode's)

$$\frac{d}{dt}c = N \cdot r(c), \quad y = h(c)$$

- Measurement  $y$ 
  - Some reaction rates  $r_i$
  - Some species concentrations  $c_i$

• Reaction kinetics

$$r = \hat{r} \frac{c_1^{\nu_1}}{K_1^{\eta_1} + c_1^{\eta_1}} \cdots \frac{c_n^{\nu_n}}{K_n^{\eta_n} + c_n^{\eta_n}}$$

- Known: Reaction & Hill-term orders  $\nu$  &  $\eta$

**Aim: Infer the parameters  $K$  &  $\hat{r}$  based on measurement  $y$  (output)**

## Method

### 1. Model extension [2]

Introduce new dynamic variables for

- Reactions rates  
 $\frac{d}{dt} \log(r) \Rightarrow \dot{r} = f(c, m, r)$
- Denominators (Hill variables)  
 $m = K^\eta + c^\eta \Rightarrow \dot{m} = f(c)$

$\Rightarrow$  Extended system:  
Parameter independent & linear output

$$\dot{x} = f(x), \quad y = C \cdot x$$

$\Rightarrow$  Initial conditions  $\hat{=}$  parameters

### 2. State reconstruction [3]

Use measurement to estimate new states

- Non-linear observer with *error-gain*  $L$   
 $\dot{\hat{x}} = f(\hat{x}) + L(y - \hat{y}), \quad \hat{y} = h(\hat{x})$
- **Caution:**  $L$  ill-conditioned if not well observable

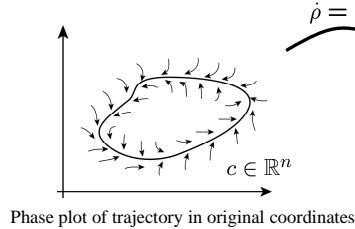
### 3. Parameter estimation

Use definition of extended variables

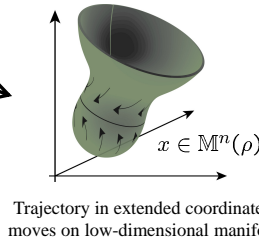
- Reaction rates  $\Rightarrow$  nominal rates  $\hat{r}$
- Hill variables  $\Rightarrow$  Hill constants  $K$

## Illustration of the method

### 1. Model extension



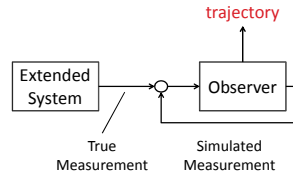
$$\dot{\rho} = 0$$



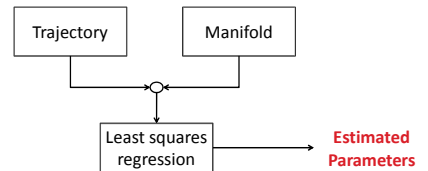
Model extension

- Higher dimensional space  
 $\Rightarrow$  Trajectory on manifold
- Shape of manifold
  - Defined by parameters
  - According definition extended variables
- Regression on observed trajectory  
 $\Rightarrow$  Identifies parameters

### 2. State reconstruction



### 3. Parameter estimation



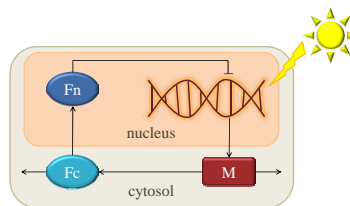
## Example

### Circadian rhythm in neurospora

- Oscillations according to day-night cycle

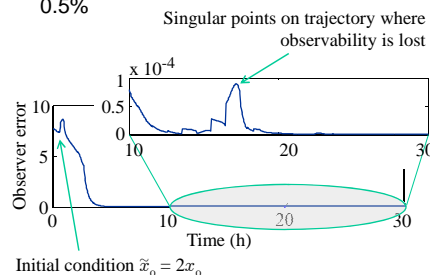
**Model** [3]

- Dynamic gene regulation model
- 3 species, 3 mass action & 3 Hill reactions  $\Rightarrow$  **9 unknown parameters**



### Results

- Observer converged
- Parameter estimate accurate, error < 0.5%



## Important Advantages

- **Decoupling** of state & parameter estimation
- *Identifiability* can be analyzed in terms of *observability*
- Measurement of all states (species concentrations) **not generally necessary**

## Conclusion

- Allows us to identify models & experiments for which the estimation is possible
- Very accurate estimation under noise free conditions

**Parameter estimation can benefit from observability based approach**

## Outlook

- Application to models of metabolic pathways, signal transduction and gene regulation
- Hybrid observer design: Continuous simulation & discrete updates
- Treating noise: e.g. Kalman Filters, error propagation, ...

## References

- (1) Peifer, M & Timmer, J, *IET Syst Biol*, 1(2):78–88 (2007)
- (2) Farina, M, Findeisen, R, Bullinger et al., P, *45th IEEE CDC*, 2104–2109 (2006)
- (3) Vargas, A & Moreno, JA, *Int J Contr*, 78:247–253 (2005)
- (4) Leloup, JC, Gonze, D, & Goldbeter, A, *J Biol Rhythms*, 14(6):433–444 (1999)

## Acknowledgements

Supported by the Science Foundation Ireland (SFI) grant 03/RP1/1382