

# Model inference from protein time-course in Hematopoietic Stem Cells (HSC)

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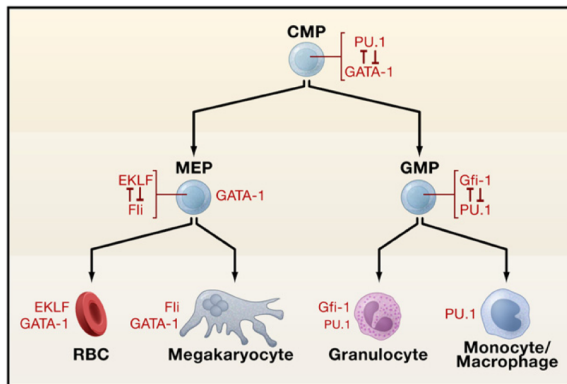
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# Introduction

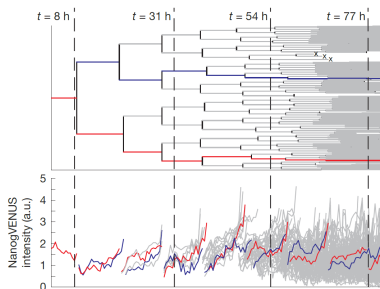
- Dynamics of hematopoietic stem cell maturation cell from Common Myeloid Progenitor (CMP) to Megakaryocyte-Erythroid Progenitor (MEP) and Granulocyte-Macrophage Progenitor (GMP)



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# Introduction (cont'd)

- ▶ Assumed cross-inhibition dynamics between Pu.1 and Gata1 in cell maturation fate:
  - ▶ Dynamics is assumed to be a bistable toggle-switch system
  - ▶ Lineage decision is a stochastic process resulting in uneven yield of MEP and GMP (70% : 30%)
- ▶ Analysis on single-cell time-lapsed data to infer parameters of this dynamics



# Problems

- ▶ Stochasticity in single cell resolution is more punctuated
- ▶ Tree structure of the data add ore complexity: inheritance of information during inference process is not trivial

# Ideas

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- ▶ Sequential Monte Carlo simulations along the time-apsed data to infer "good" parameters
- ▶ **problem:** Overfitting due to single-cell biased
- ▶ **solution:** Inference across cell lineages
- ▶ Inferred parameters from all simulated lineages are represented as distribution
- ▶ Final inferred parameters are expected value  $E$  of the distribution

# Particle Filtering

A particle  $K$  is defined as a triple of trajectory  $X$  (*time series data*), parameter set  $\theta$  and assumed model  $M$ ,

$$K := (X, \theta, M) \tag{1}$$

- ▶  $X$  describes the simulation trajectory
- ▶  $M$  describes the model of the simulation
- ▶  $\theta$  describes the parameters of the simulation's model

# Particle Filtering (7)

# Particle Filtering: algorithm

1. Initialization of parameters  $\theta$ .
2. Input of data  $\mathcal{D}$ .
3. Particle filtering routine:

3.1 Generation of initial particles for step i

$$K_i := (K_{i1}, K_{i2}, \dots, K_{im}) \quad (2)$$

3.2 Simulation run of each particle  $K_{ij}$

3.3 Weighting of each particle. The weight is a function of the probability of observing the data given the simulation result.

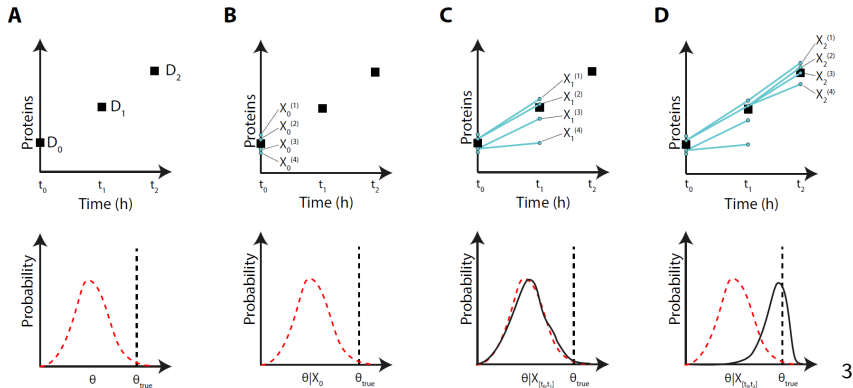
$$w_i^k = P(D_i | X_i^k) = \mathcal{N}(\mathcal{D}_i | X_i^k) \quad (3)$$

3.4 Parameter update for every K,

$$\theta^k \propto P(\theta | X_{[t_0, t_i]}^k) \quad (4)$$

4. Model comparison.

# Particle Filtering: visualization



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