

LoopDetect Example

This script reproduce examples given in the manual and manuscript

Resources:

[1] LoopDetect MATLAB package: <https://de.mathworks.com/matlabcentral/fileexchange/81928-loopdetect/>

[2] Quick tutorial: https://kabaum.gitlab.io/loopdetect_for_matlab/workflow_LoopDetect_Matlab.html

[3] Glossary of functions: https://kabaum.gitlab.io/loopdetect_for_matlab/

0. Start

0.1. Cleaning the environment

```
clear; close all; clc;
```

0.2. Installation and import

Download and unzip the content of the folder 'LoopDetect_for_Matlab'. Within the MATLAB session, navigate to this folder and work there or add the path of the folder to MATLAB's search path for the current MATLAB session by MATLAB's addpath() function. Depending on where you stored the folder, its name could be something like '/Users/Desktop/LoopDetect' on Mac or 'C:\matlab\LoopDetect' on Windows.

```
% Retrieve the LoopDetect folder location when having navigated to the folder
% within the MATLAB session.
LoopDetect_Folder_Name = fullfile(pwd, '.', 'LoopDetect_2025', 'src',
'loopdetect_for_matlab');
LoopDetect_Folder_Name =
char(java.io.File(LoopDetect_Folder_Name).getCanonicalPath); % normalize path
addpath(LoopDetect_Folder_Name);
```

1. First example

1.1. Loop characteristics

4 species, positive feedbacks. Firstly, we assigned 1 to all linear parameters.

```
s_star=[1,1,1,1]';
klin=ones(1,8); knonlin=[2.5,3];
loop_list=find_loops_vset(@(x)func_POSm4(1,x,klin,knonlin),s_star,10);
disp(loop_list{1})
```

loop	length	sign
[[4 1 2 3 4]]	4	-1
[[4 2 3 4]]	3	1
[[1 1]]	1	-1
[[2 2]]	1	-1
[[3 3]]	1	-1
[[4 4]]	1	-1

```
first_loop=loop_list{1}.loop{1}
```

```
first_loop = 1×5  
4 1 2 3 4
```

1.2. Solving the ODE model

Now, we assigned the parameters accordingly to the manuscript, attempt to reproduce the results.

```
%klin=[165,0.044,0.27,550,5000,78,4.4,5.1];  
%knonlin=[0.3,2];  
  
klin =[150, 0.04, 0.3, 500, 5000, 80, 4, 5];  
knonlin=[0.3,2]  
  
knonlin = 1×2  
0.3000 2.0000  
  
tspan = linspace(0, 13, 13001);  
  
% Add initial value. Previously: ones(1,4)  
initial_values = [1,2,3,4];  
%[t,sol]=ode15s(@(t,x)func_POSm4(t,x,klin,knonlin),[0,11], initial_values); %  
previous time=[0,50]  
  
opts = odeset('RelTol',1e-6,'AbsTol',1e-9); % closer to typical SciPy accuracy  
[t,sol] = ode15s(@(t,x) func_POSm4(t,x,klin,knonlin), tspan, initial_values, opts);  
s_star=sol(end,:); %the last point of the simulation is chosen
```

1.3. Calculating the Jacobian matrix

The functions `numerical_jacobian()` and `numerical_jacobian_complex()` provide numerical estimates of the Jacobian matrix of an ODE system at a chosen state vector s_* . They implement, respectively, a **finite-difference method using real perturbations** and the **complex-step method**, the latter offering higher accuracy due to the absence of subtractive cancellation errors (see Martins *et al.*, 2003) and making use of MATLAB's built-in support for complex arithmetic.

The function handle `f` (in the example derived from `func_POSm4`, the positive-feedback chain model of Baum *et al.*, 2016) must refer to a function that returns the vector of time derivatives,

$$f_i(s) = \frac{dS_i}{dt}.$$

When used with `numerical_jacobian_complex()`, this function is required to depend **only** on the state variables. Any additional dependencies—such as model parameters—must be fixed beforehand so that `f` effectively maps only the variable vector s to its corresponding derivative vector.

```
%klin=[165,0.044,0.27,550,5000,78,4.4,5.1];  
klin =[150, 0.04, 0.3, 500, 5000, 80, 4, 5];  
knonlin=[0.3,2];  
j_matrix=numerical_jacobian_complex(@(s)func_POSm4(1,s,klin,knonlin),...  
s_star);
```

```
signed_jacobian=sign(j_matrix)
```

```
signed_jacobian = 4x4
-1     0     0    -1
 1    -1     0     1
 0     1    -1     0
 0     0     1    -1
```

1.4. Computing all feedback loops and useful functions for loop search

```
loop_list=find_loops(j_matrix)
```

loop_list = 6x3 table

	loop	length	sign
1	[4,1,2,3,4]	4	-1
2	[4,2,3,4]	3	1
3	[1,1]	1	-1
4	[2,2]	1	-1
5	[3,3]	1	-1
6	[4,4]	1	-1

Single loops can be examined by entering the corresponding entry.

```
for i=1:3
    disp(loop_list.loop{i})
end
```

```
4     1     2     3     4
4     2     3     4
1     1
```

The function `loop_summary()` provides a convenient report on total number of loops, subdivided by their lengths and signs.

```
disp(loop_summary(loop_list))
```

	length_1	length_2	length_3	length_4
total	4	0	1	1
negative	4	0	0	1
positive	0	0	1	0

One can filter the loop list for loops containing specific variables, for example the one with index 2:

```
noi = 2;
loops_with_node2=loop_list(...
    cellfun(@(z) ismember(noi,z),loop_list.loop),:)
```

```
loops_with_node2 = 3x3 table
```

	loop	length	sign
1	[4,1,2,3,4]	4	-1
2	[4,2,3,4]	3	1
3	[2,2]	1	-1

Search a loop list for loops containing specific edges defined by the indices of the ingoing and outgoing nodes. This example returns the indices of all loops with a regulation of node 3 by node 2. These are only two here.

```
loop_edge_ind=find_edge(loop_list,2,3);
loops_with_edge_2_to_3=loop_list(loop_edge_ind,:)
```

`loops_with_edge_2_to_3 = 2x3 table`

	loop	length	sign
1	[4,1,2,3,4]	4	-1
2	[4,2,3,4]	3	1

```
for i=1:2
    disp(loops_with_edge_2_to_3.loop{i})
end
```

```
4     1     2     3     4
4     2     3     4
```

Saving and reading loop lists from files can be done using MATLAB's `save()` and `load()` functions. They keep the correct data format, but objects have to be retrieved from a struct.

```
save('loop_list_example.mat', 'loops_with_node2')
loaded_loops_with_node2=load('loop_list_example.mat')
```

```
loaded_loops_with_node2 = struct with fields:
    loops_with_node2: [3x3 table]
```

```
% access the loaded data table from the struct (might not be required
% in earlier MATLAB versions)
loaded_loops_with_node2.loops_with_node2
```

`ans = 3x3 table`

	loop	length	sign
1	[4,1,2,3,4]	4	-1
2	[4,2,3,4]	3	1
3	[2,2]	1	-1

Reading and writing loop lists to tabular format can be performed via MATLAB's `writetable()` and `readtable()` functions. Here, we choose tabs as delimiters. Note that the formatting is lost.

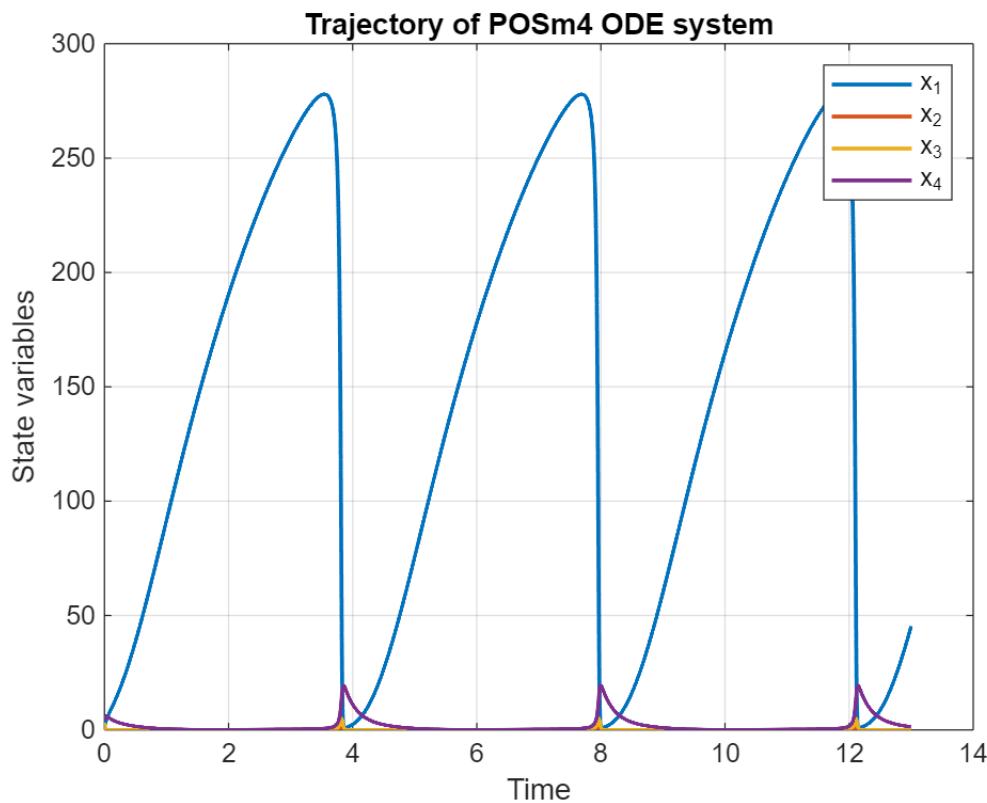
```
writetable(loops_with_node2,'loop_list_example.txt','Delimiter','\t')
loops_with_node2_readin = readtable('loop_list_example.txt')
```

```
loops_with_node2_readin = 3x7 table
```

	loop_1	loop_2	loop_3	loop_4	loop_5	length	sign
1	4	1	2	3	4	4	-1
2	4	2	3	4	NaN	3	1
3	2	2	NaN	NaN	NaN	1	-1

1.5. Plots

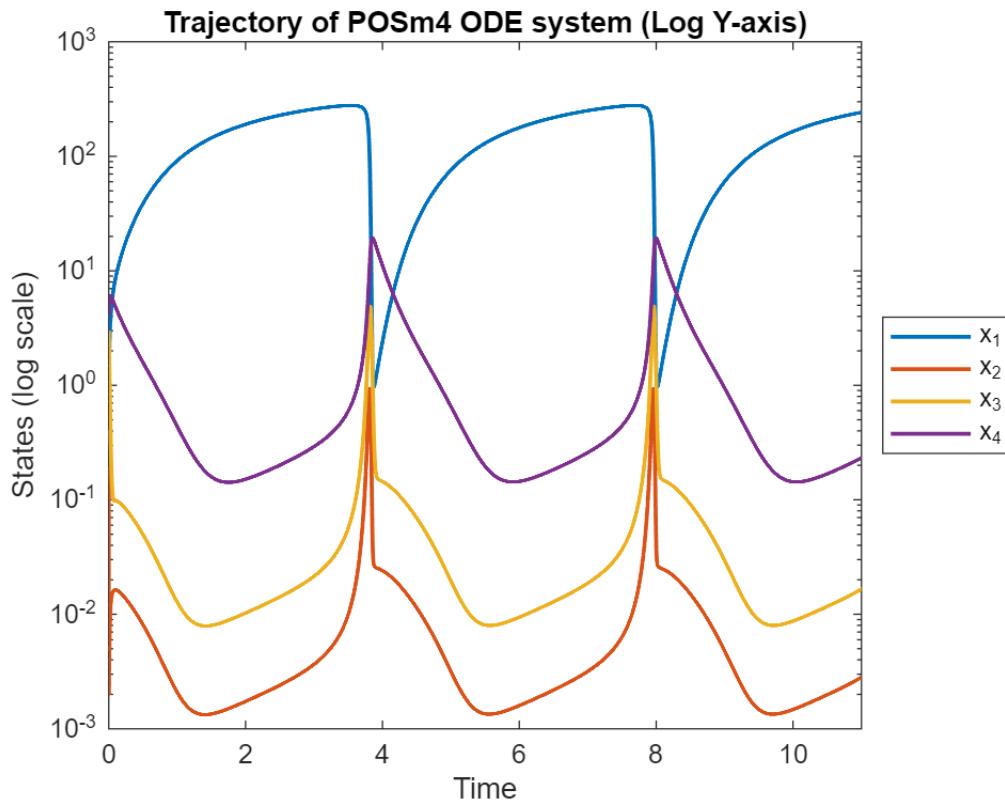
```
figure;
plot(t, sol, 'LineWidth', 1.5);
xlabel('Time');
ylabel('State variables');
title('Trajectory of POSm4 ODE system');
legend('x_1','x_2','x_3','x_4');
grid on;
```



Rescale y-axis to log-scale.

```
figure;
semilogy(t, sol, 'LineWidth', 1.5);
xlabel('Time');
ylabel('States (log scale)');
xlim([0,11]);
title('Trajectory of POSm4 ODE system (Log Y-axis)');
```

```
legend('x_1','x_2','x_3','x_4','Location','eastoutside'); % southeast
```



2. Second example

Calcium oscillation

```
function [dx] = func_gold90(t,x,klin,knonlin)
    dx=zeros(2,1);
    %J=jacob_gold90(t,x,klin,knonlin);
    dx(1)= klin(1)+klin(2)-klin(3)*x(1)^knonlin(4)/
(knonlin(1)^knonlin(4)+x(1)^knonlin(4))+klin(4)*x(2)^knonlin(5)*x(1)^knonlin(6)/
((knonlin(2)^knonlin(5)+x(2)^knonlin(5))*(knonlin(3)^knonlin(6)+x(1)^knonlin(6)))
+klin(5)*x(2)-klin(6)*x(1);
    dx(2)=klin(3)*x(1)^knonlin(4)/
(knonlin(1)^knonlin(4)+x(1)^knonlin(4))-klin(4)*x(2)^knonlin(5)*x(1)^knonlin(6)/
((knonlin(2)^knonlin(5)+x(2)^knonlin(5))*(knonlin(3)^knonlin(6)+x(1)^knonlin(6))-
klin(5)*x(2);
end
```

Initial values:

```
initial_conditions_calcium = [0.3920, 1.6456];
klin_calcium = [1, 7.3, 65, 500, 1, 10];
kn_calcium = [1, 2, 0.9];
```

```
n_calcium = [2, 2, 4];
knonlin_calcium = [1, 2, 0.9, 2, 2, 4]
```

```
knonlin_calcium = 1×6
1.0000    2.0000    0.9000    2.0000    2.0000    4.0000
```

```
time_points = linspace(0, 3, 31);
```

Solve:

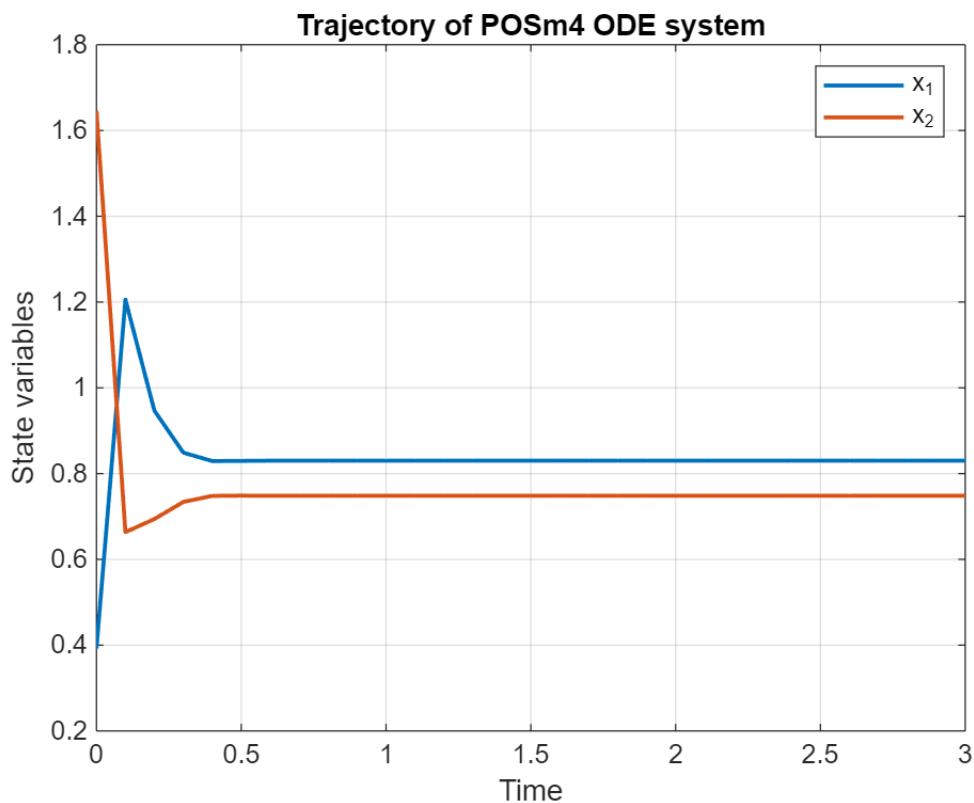
```
opts = odeset('RelTol',1e-6,'AbsTol',1e-9); % closer to typical SciPy accuracy
[t,sol] = ode15s(@(t,x) func_gold90(t,x,klin_calcium,knonlin_calcium), time_points,
initial_conditions_calcium, opts);
s_star=sol(end,:); %the last point of the simulation is chosen
```

Visualize:

```
figure;
plot(t, sol, 'LineWidth', 1.5);
xlabel('Time');
ylabel('State variables');
title('Trajectory of POSm4 ODE system');
legend('x_1','x_2','x_3','x_4');
```

Warning: Ignoring extra legend entries.

```
grid on;
```



5. Export *.mlx to *.html

```
path = export("MATLAB/test mlx", "MATLAB/test.pdf")  
  
path =  
'MATLAB\test.pdf'  
  
mdfile = export("MATLAB/test mlx", "MATLAB/test.md", Format="markdown",  
EmbedImages=true, ...  
AcceptHTML=true)  
  
mdfile =  
'MATLAB\test.md'
```