Closed-loop model discrimination.

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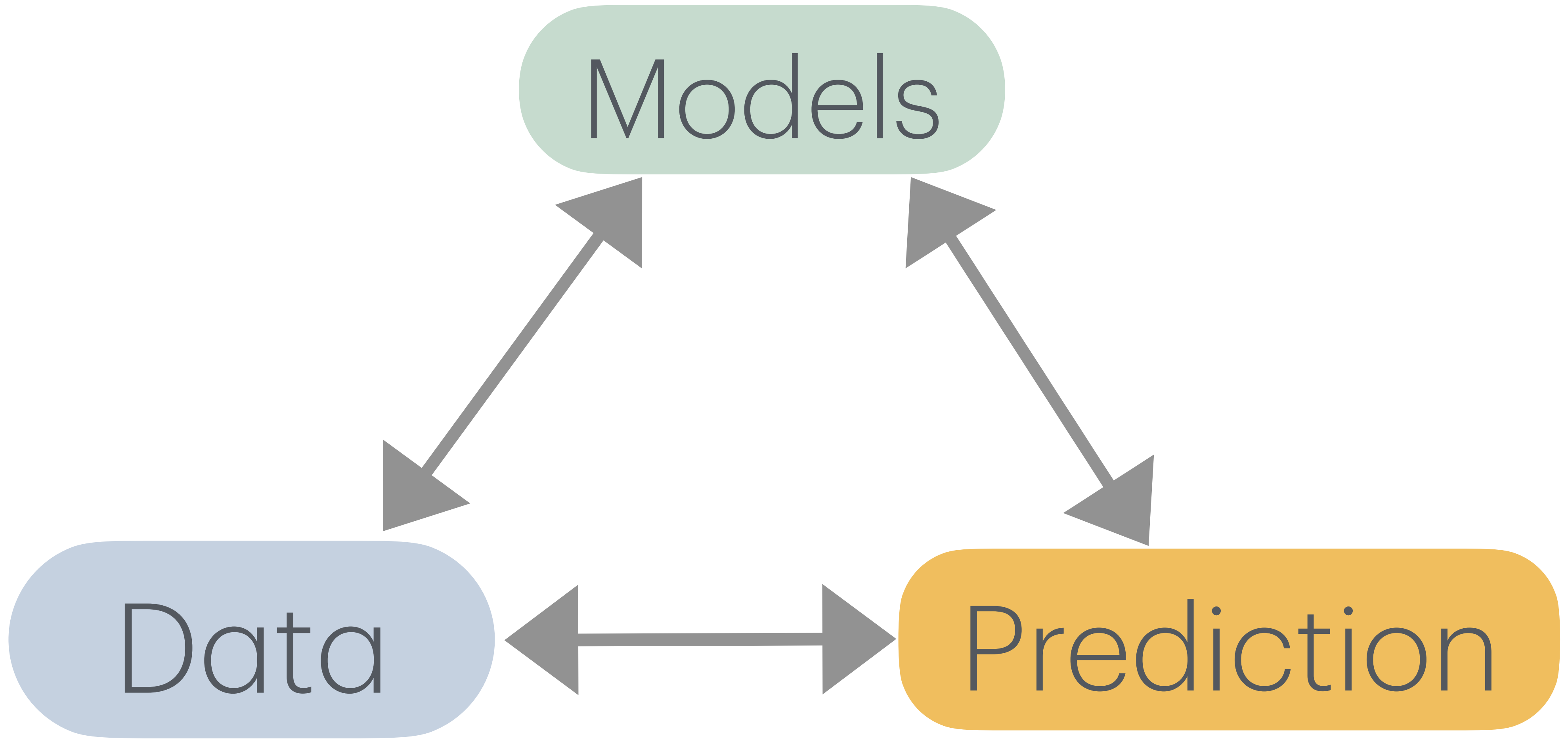

ICMNS, MCGill University — 4/6/2026

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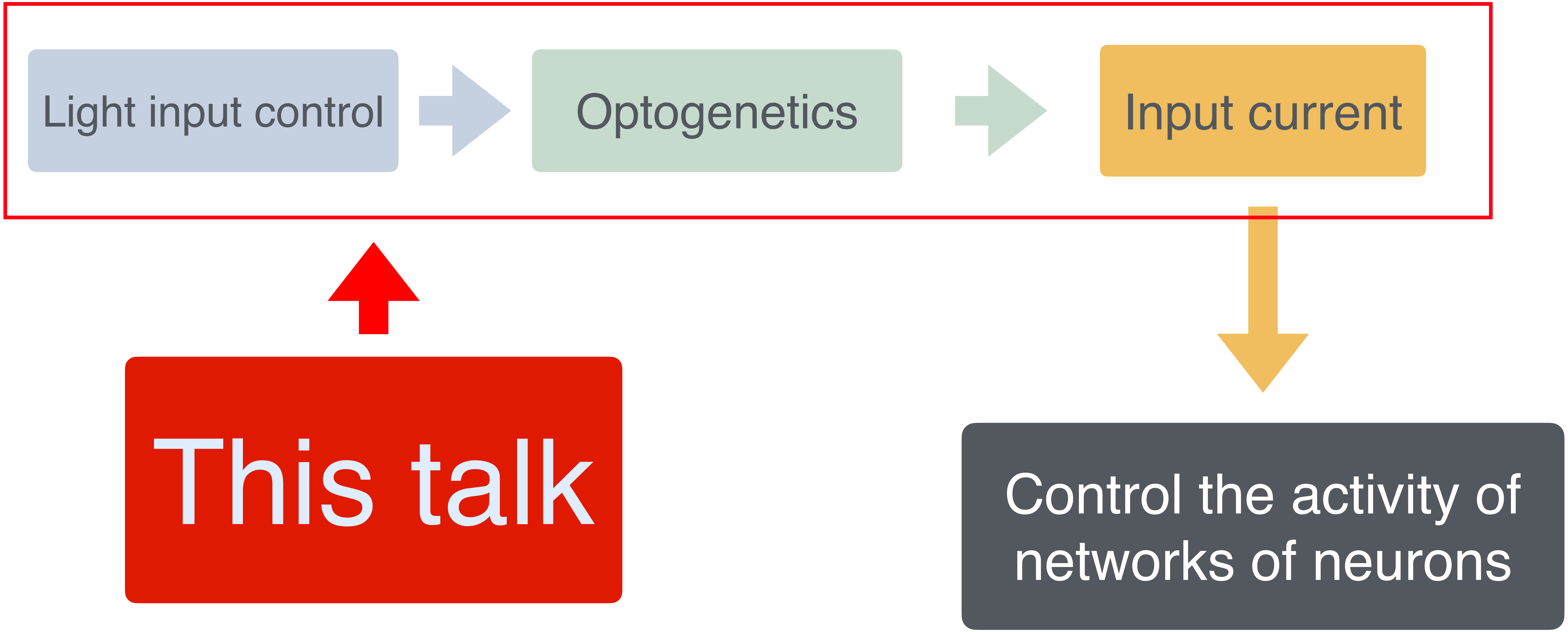
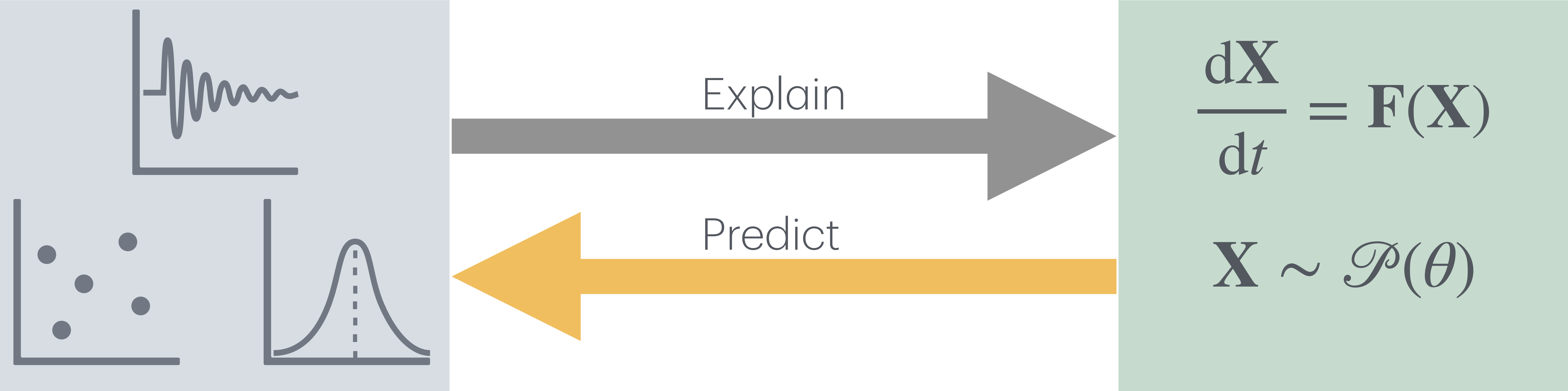
Preprint arXiv:2603.00709

Why model discrimination?



Data — Models

Data **Models**



$$\frac{\mathrm{d}\mathbf{X}}{\mathrm{d}t} = \mathbf{F}(\mathbf{X})$$

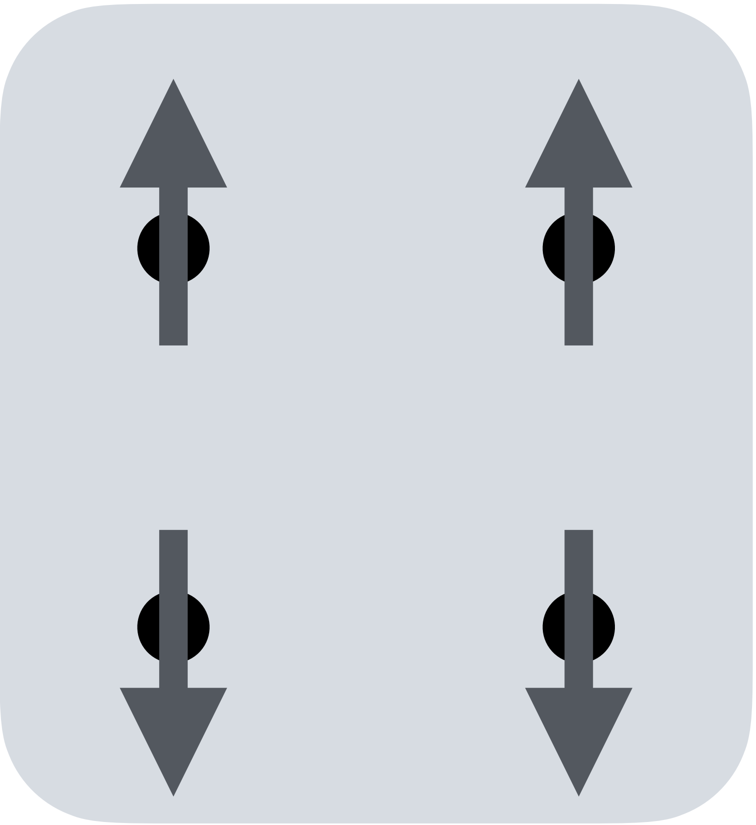
$$\mathbf{X} \sim \mathscr{P}(\theta)$$

- Measurements from an experiment
- Observation of a process

- Differential equations
- Probabilistic models

More than one model…

Observed system



Average magnetization

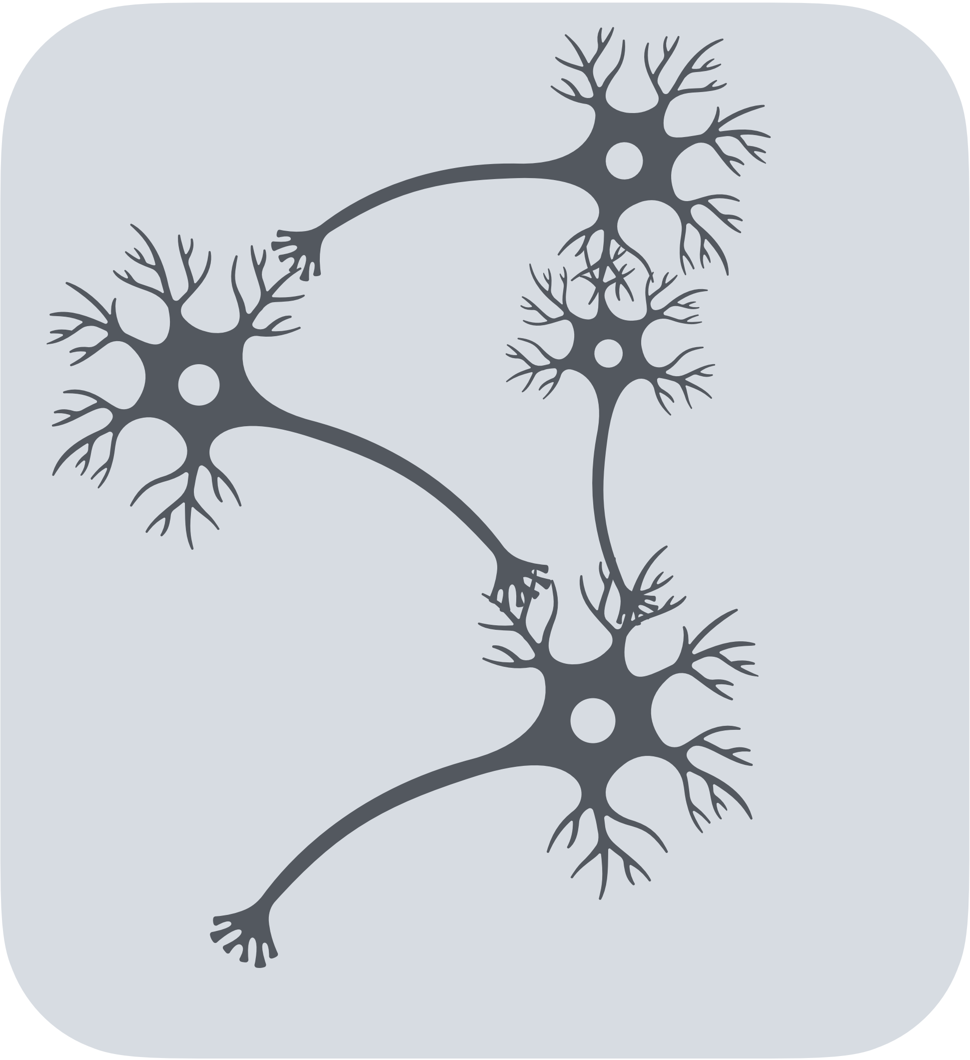
Models

$$\mathcal{H} = \sum_{<i,j>} J_{ij} \sigma_i \sigma_j$$

$$\mathcal{H} = \sum_{<i,j>} T_{ij} c_\sigma^\dagger c_\sigma + \alpha \sum_i n_\sigma^\dagger n_\sigma$$

More than one model…

Observed system



Spike times

Models

$$\tau \dot{V}_i = V_i^2 + \eta_i + \sum_{j=1}^{N} A_{ij}(V_i - V_j) + I_i^{\text{ext}}(t)\,,$$

$$V_i(t) = V_{\text{th}} \rightarrow V_i(t) = -\,V_{\text{th}}$$

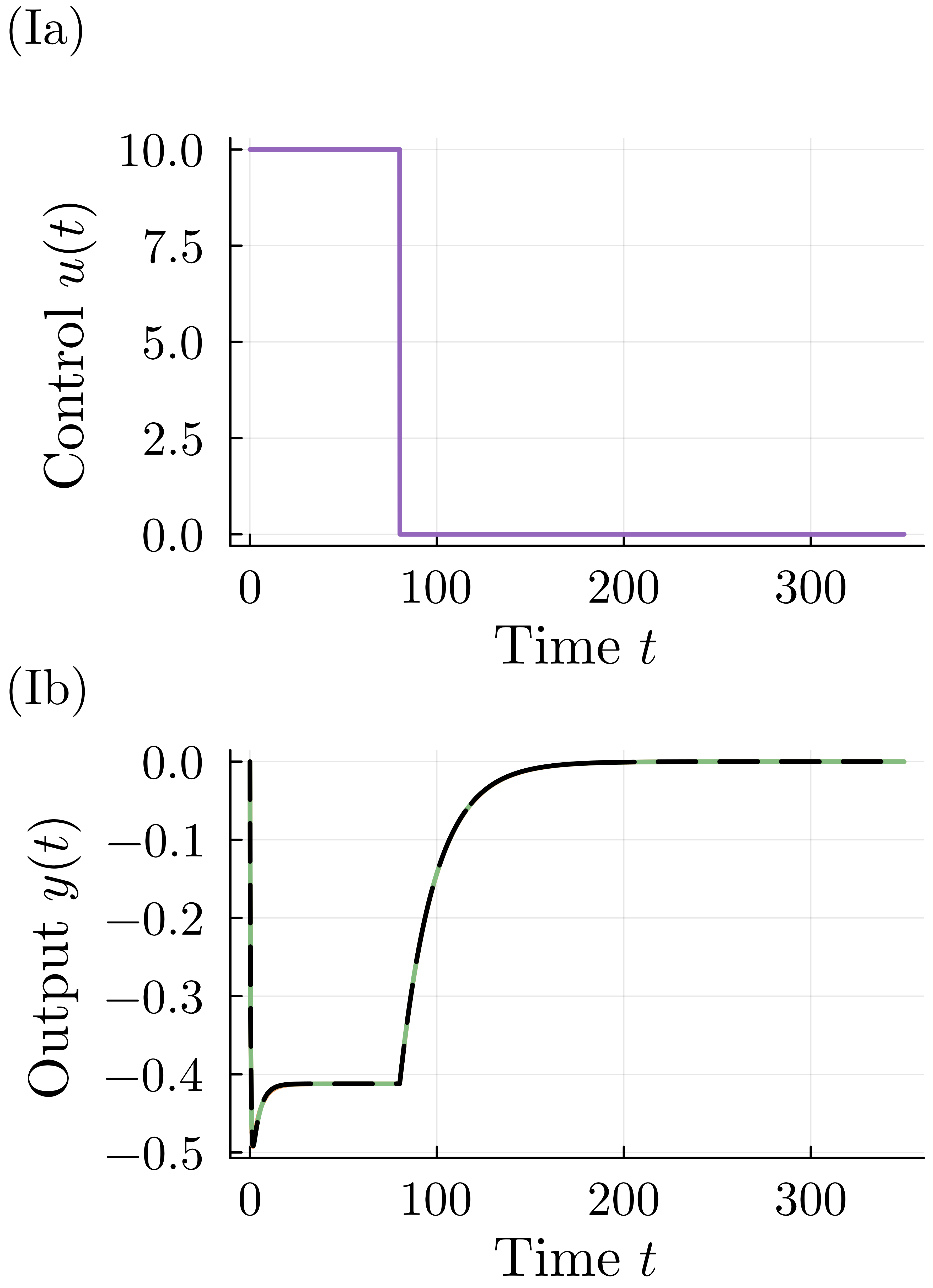
$$\dot{V}_i = V_i - \frac{V_i^3}{3} - w + \alpha I_i^{\text{ext}}(t)\,,$$

$$\tau \dot{w}_i = V_i + a - b w_i$$

Candidate models

$$\dot{\boldsymbol{X}}_k = \boldsymbol{F}_k\left(\boldsymbol{X}_k, u(t)\,; \boldsymbol{\Theta}_k\right)\,,$$

$$\boldsymbol{Y}_k = \boldsymbol{O}_k\left(\boldsymbol{X}_k;\, \boldsymbol{\Theta}_k\right)\,, \qquad k = 1,\ldots N\,.$$

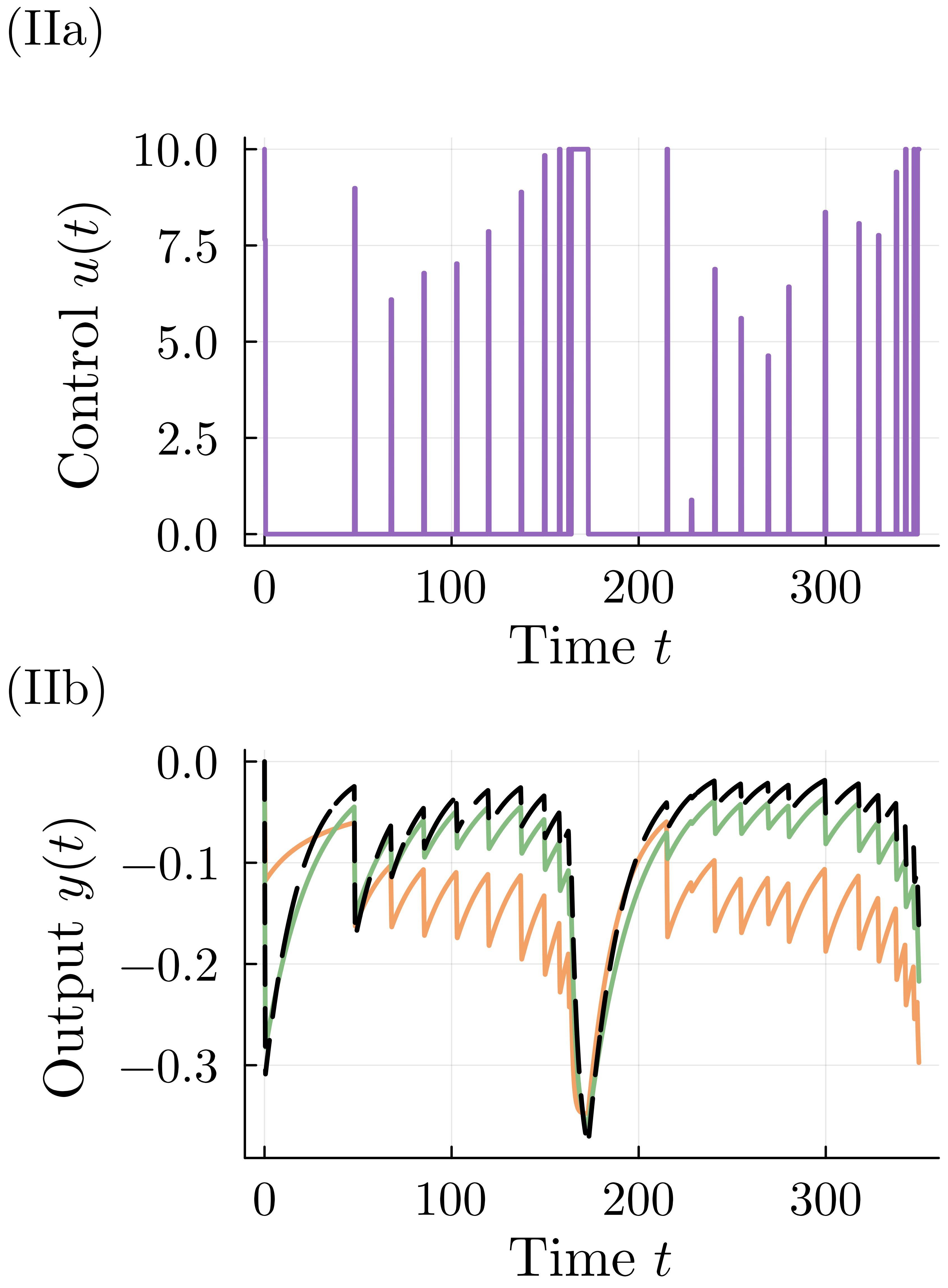


Candidate models

$$\dot{\boldsymbol{X}}_k = \boldsymbol{F}_k\big(\boldsymbol{X}_k, u(t)\,;\boldsymbol{\Theta}_k\big)\,,$$
$$\boldsymbol{Y}_k = \boldsymbol{O}_k\big(\boldsymbol{X}_k;\,\boldsymbol{\Theta}_k\big)\,, \qquad k = 1,\ldots N\,.$$

+

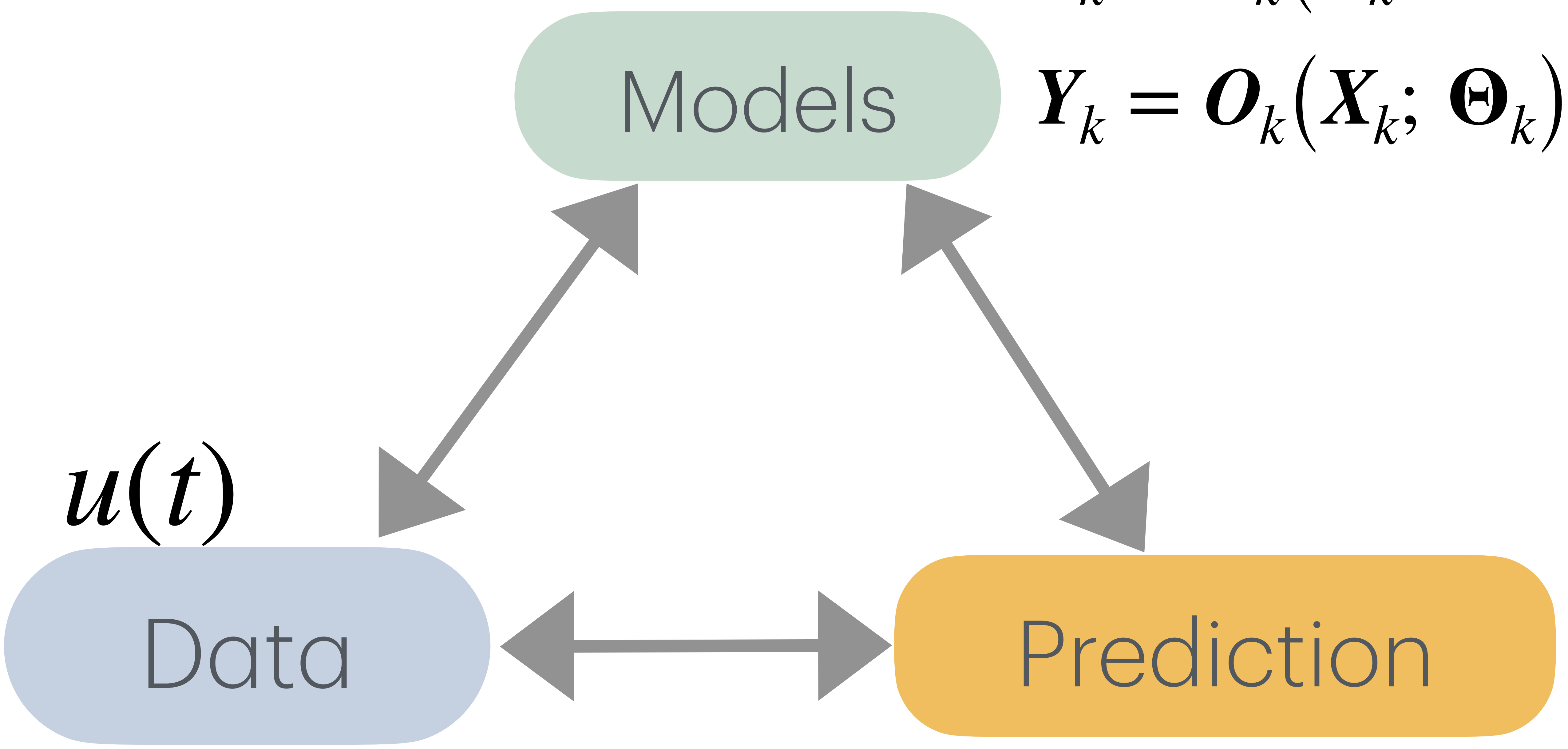
Optimal control



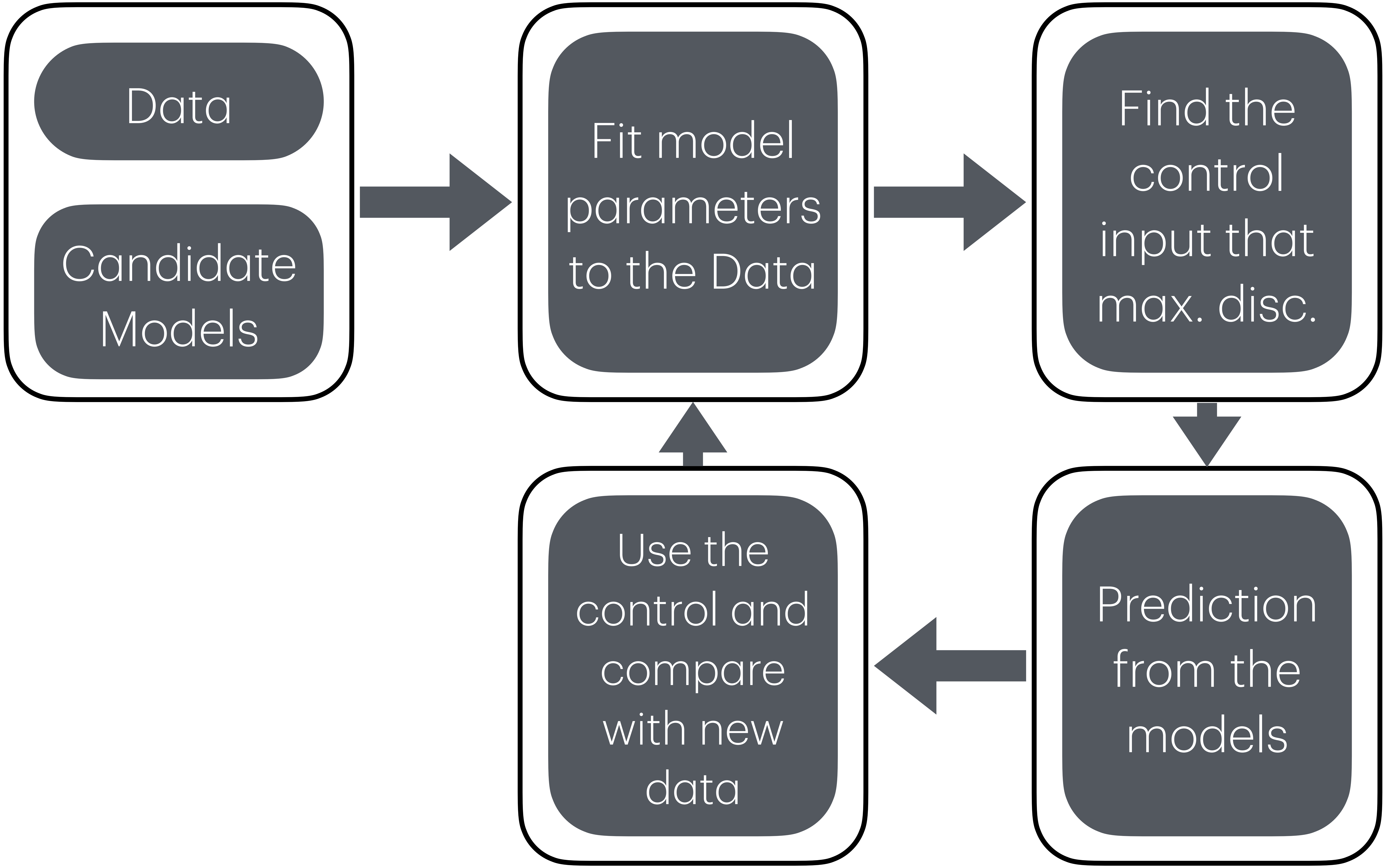
The objective

- For a set of candidate models, find control inputs that allow to choose the right model.

$$\dot{\boldsymbol{X}}_k = \boldsymbol{F}_k\left(\boldsymbol{X}_k, u(t)\,; \boldsymbol{\Theta}_k\right),$$
$$\boldsymbol{Y}_k = \boldsymbol{O}_k\left(\boldsymbol{X}_k;\, \boldsymbol{\Theta}_k\right), \qquad k = 1,\ldots N.$$



Sketch of the method



Step 0

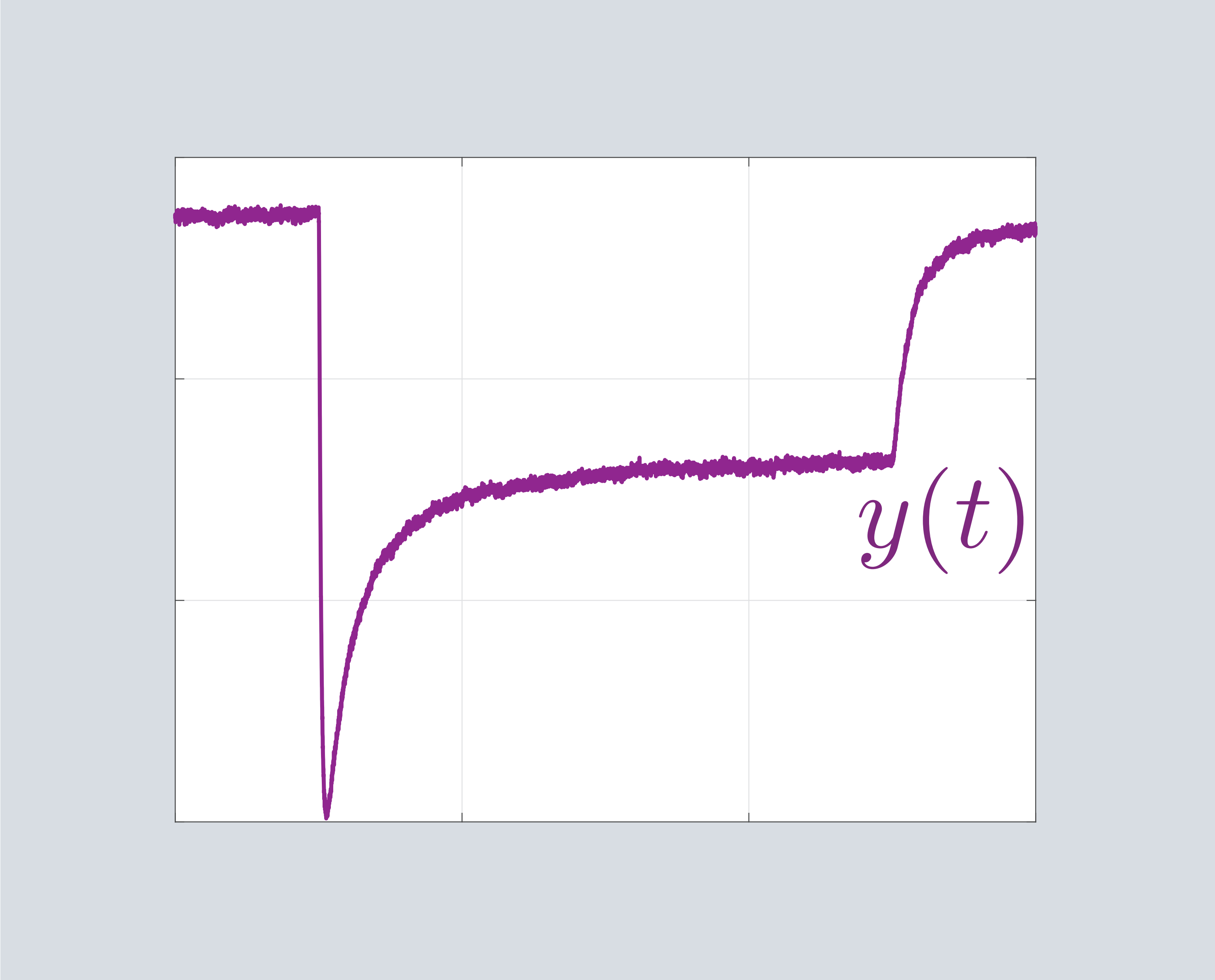
Find some candidate models!

$$\dot{\boldsymbol{X}}_k = \boldsymbol{F}_k\left(\boldsymbol{X}_k, u(t)\,; \boldsymbol{\Theta}_k\right),$$

$$\boldsymbol{Y}_k = \boldsymbol{O}_k\left(\boldsymbol{X}_k; \boldsymbol{\Theta}_k\right), \qquad k = 1,2.$$

Step 1 → Step 2

Collect some data



Known $u(t)$

Parameter fitting

$$\dot{X}_k = F_k\left(X_k, u(t)\,; \Theta_k\right),$$

$$Y_k = O_k\left(X_k;\, \Theta_k\right), \qquad k = 1,2.$$

Fitting using a loss function

$$\mathcal{L}(\Theta_k; k) = \int_0^T D\Big(\mathbf{Z}(t), \mathbf{Y}\big(X_k(t)\big)\Big)\,\mathrm{d}t$$

$$D(x, y) = \|x - y\|_2^2$$

Step 3

Optimal Control

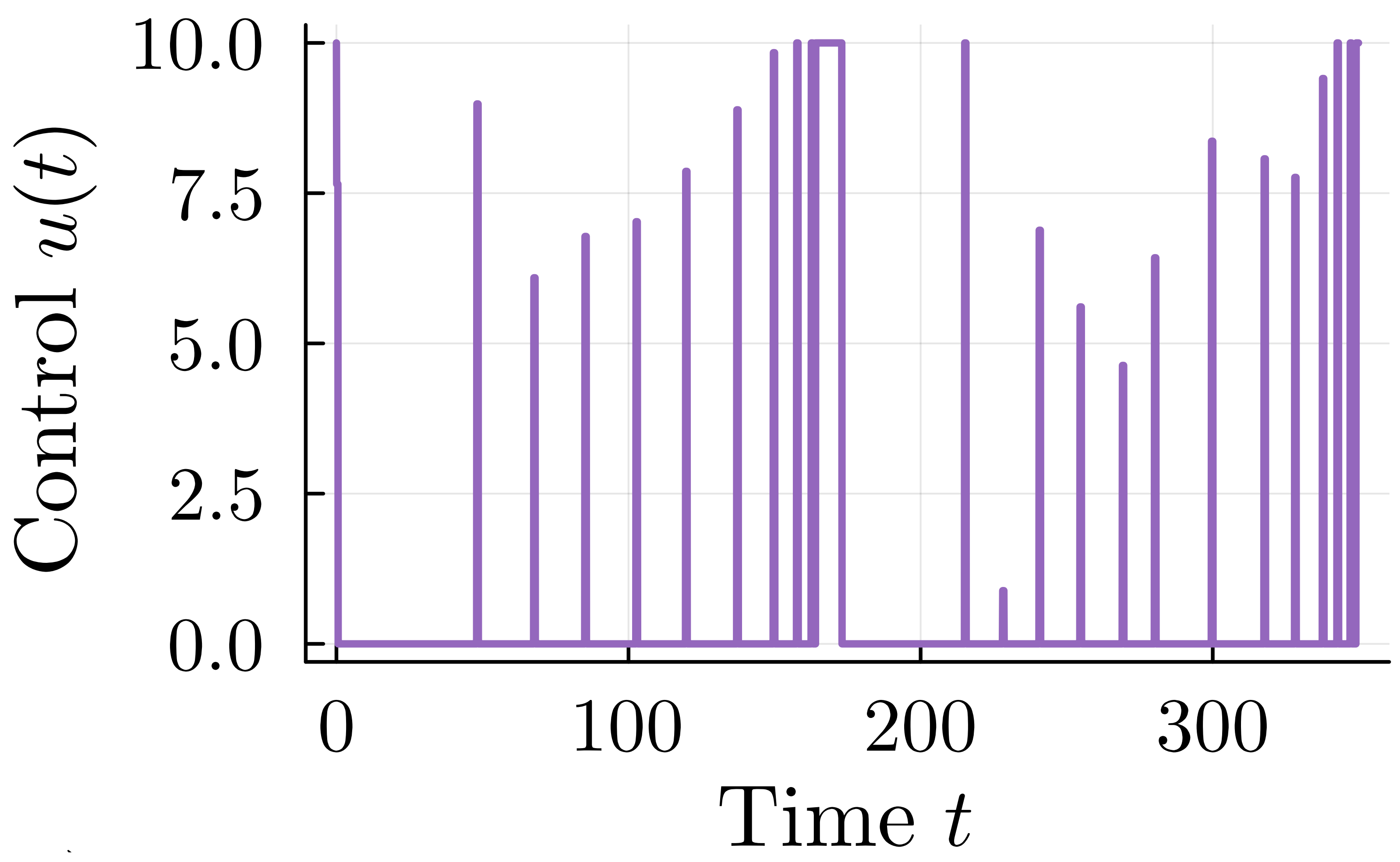
$$\mathcal{J}\big(u(t)\big) := \int_0^T \Big[D\Big(\boldsymbol{Y}_1\big(X_1(u)\big), \boldsymbol{Y}_2\big(\boldsymbol{X}_2(u)\big)\Big) - C(u)\Big]\,\mathrm{d}t$$

$$u^* = \mathrm{argmax}_u\, \mathcal{J}(u)$$

Constraint on past control signals!

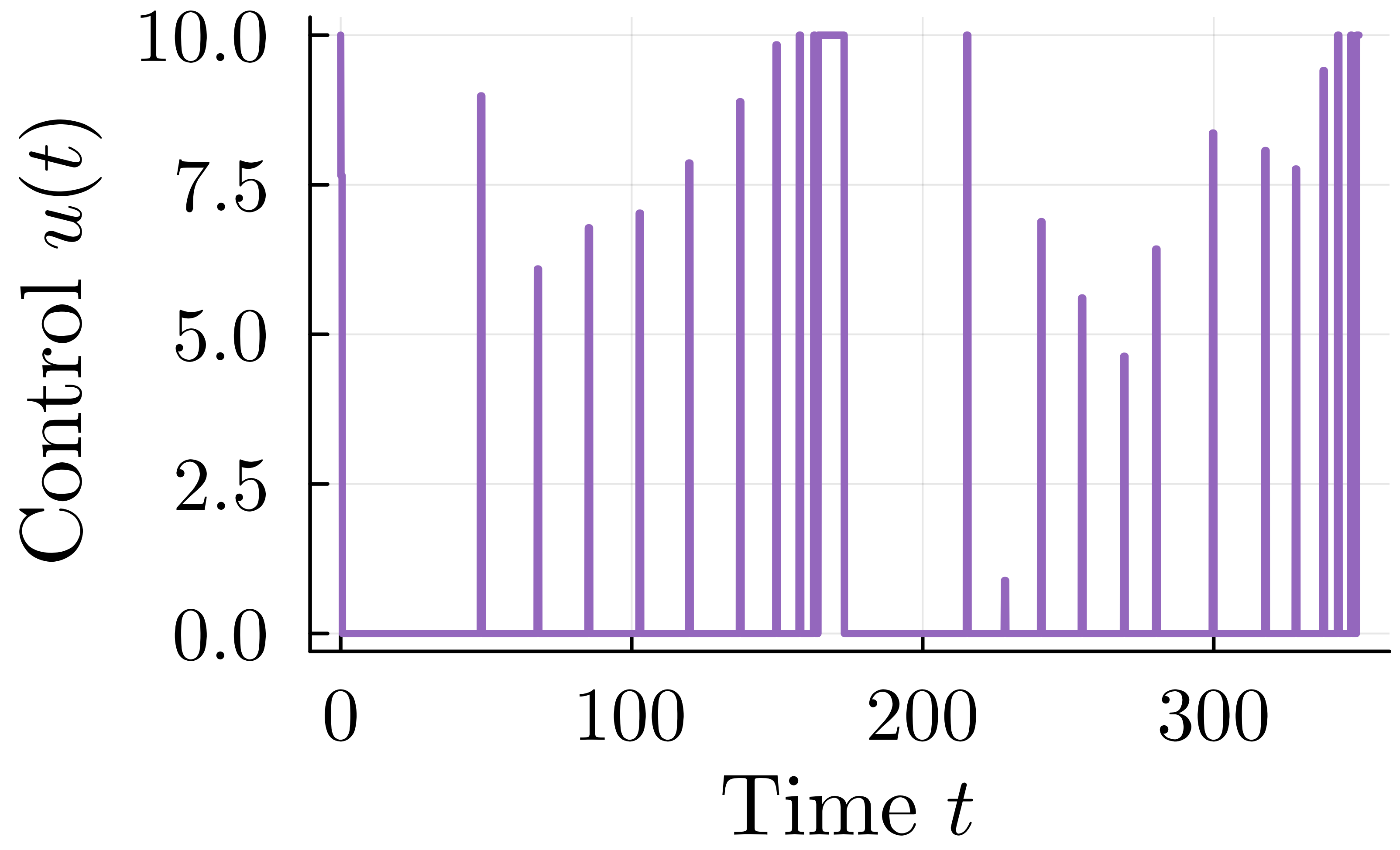
Efficiently solved using Ipopt.

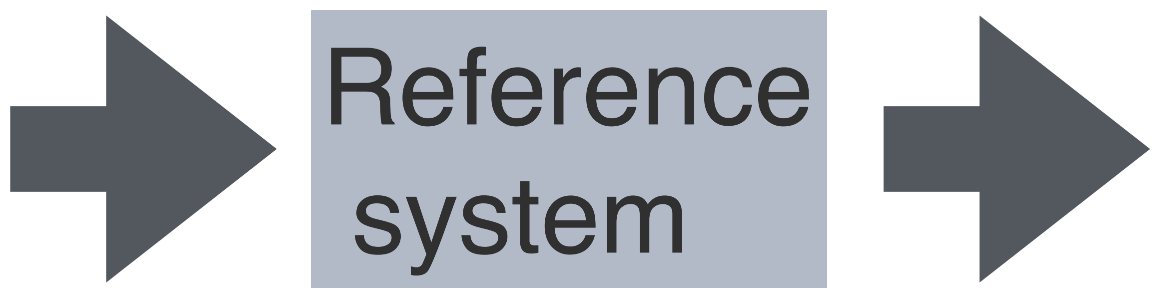
(IIa)



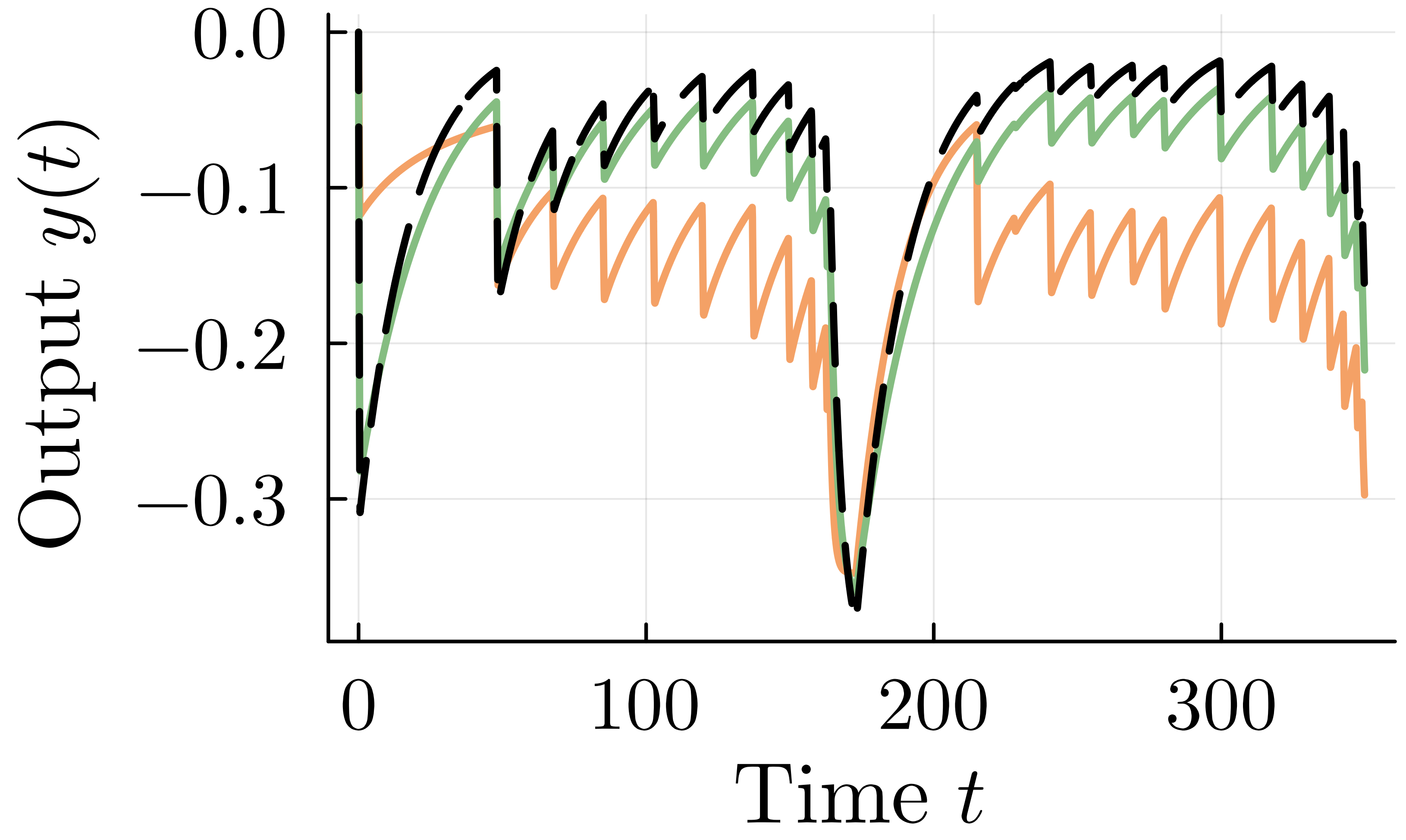
Step 4 → Step 0

(IIa)

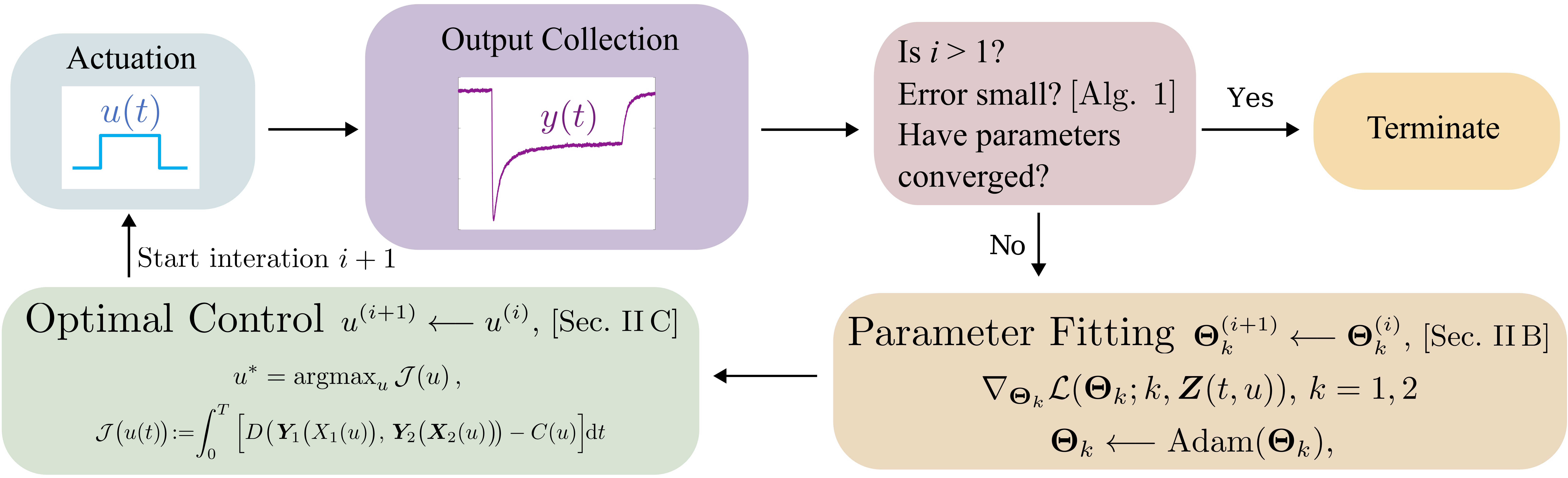




(IIb)



Method Workflow



Apply the method on an experiment

Data

Electrophysiology experiment

Candidate models

3 different models

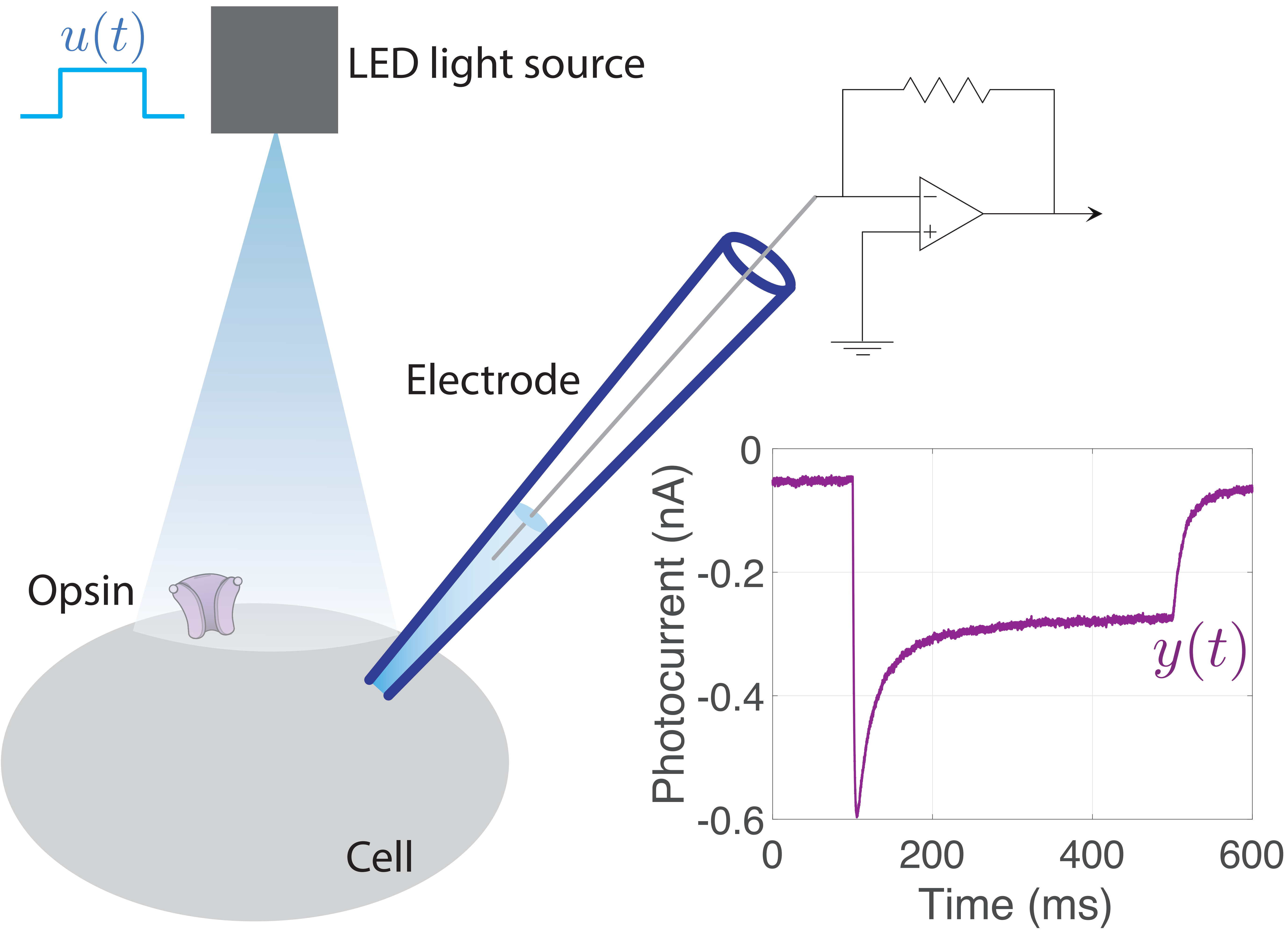
Control input

Light intensity

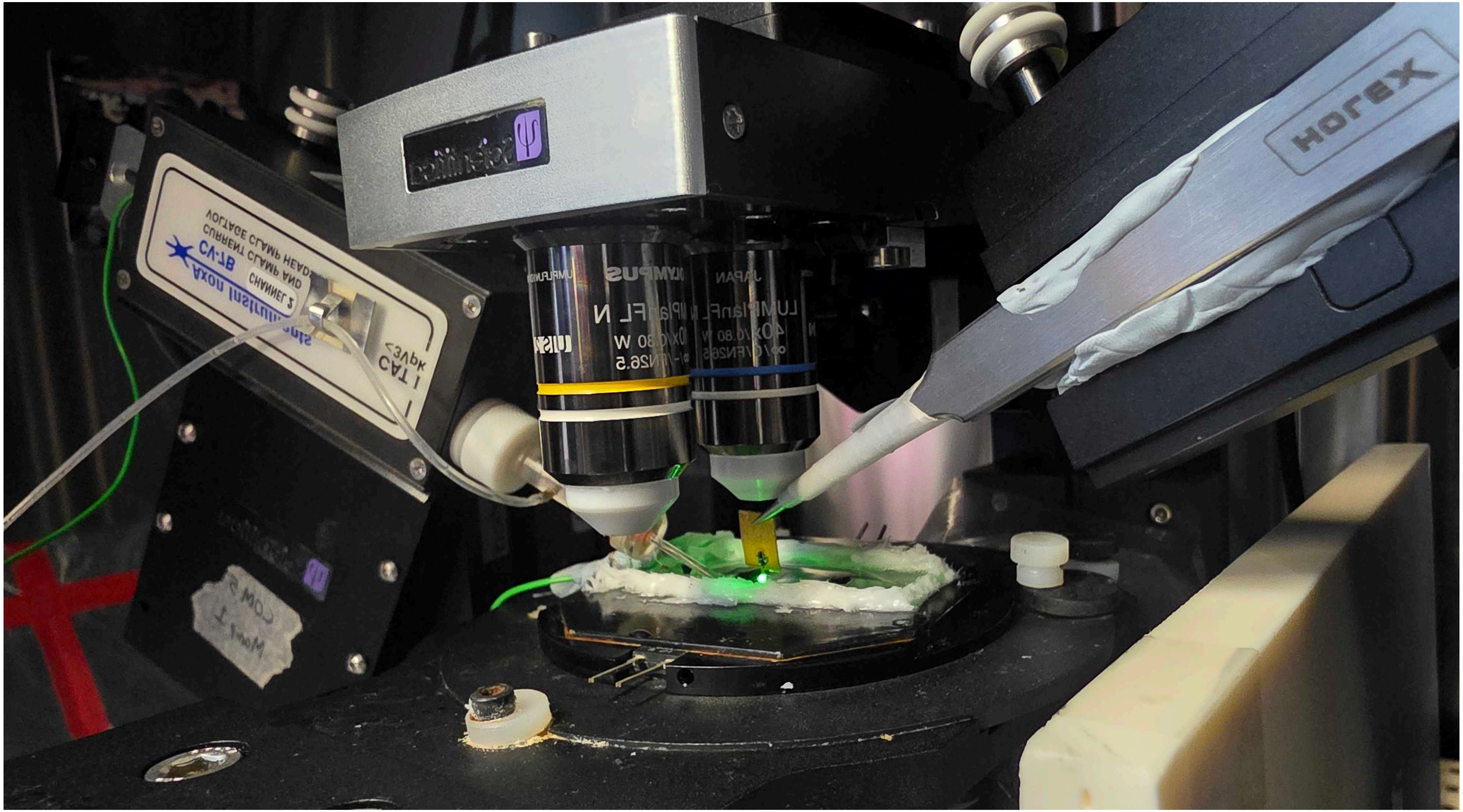
1. Numerical experiment
2. Actual experiment

Electrophysiology experiment

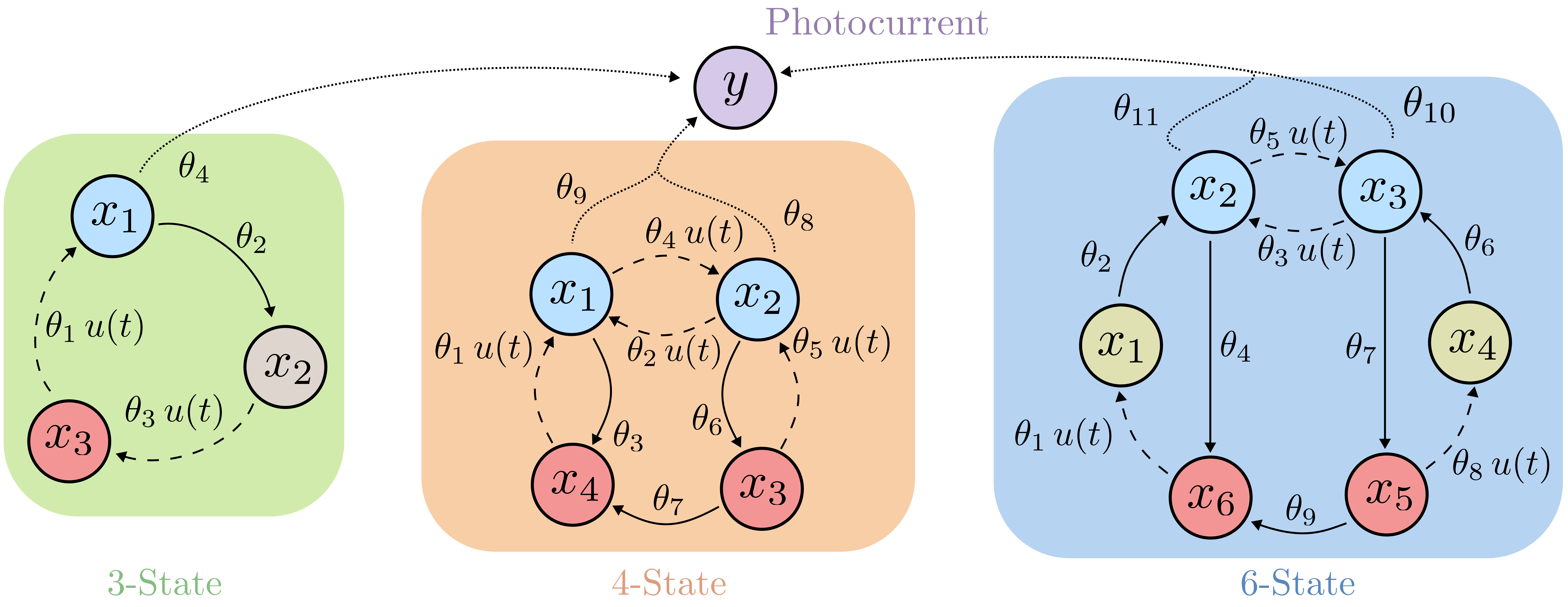
channelrhodopsin-2



Experiment



Opsin models



Evans et al. Frontiers '16

Opsin models

3-state model

$$\dot{x}_1 = \theta_1 u(t)\, x_3 - \theta_2 x_1\,,$$
$$\dot{x}_2 = \theta_2 x_1 - \theta_3 u(t)\, x_2\,,$$
$$x_3 = 1 - x_1 - x_2\,,$$
$$y = \theta_4 x_1\,.$$

4-state model

$$\dot{x}_1 = \theta_1 u(t)\, x_4 + \theta_2 u(t)\, x_2 - \left[\theta_3 + \theta_4 u(t)\right] x_1\,,$$
$$\dot{x}_2 = \theta_5 u(t)\, x_3 + \theta_4 u(t)\, x_1 - \left[\theta_6 + \theta_2 u(t)\right] x_2\,,$$
$$\dot{x}_3 = \theta_6\, x_2 - \left[\theta_7 + \theta_5 u(t)\right] x_3\,,$$
$$x_4 = 1 - x_1 - x_2 - x_3\,,$$
$$y = \theta_9\, x_1 + \theta_8\, x_2\,.$$

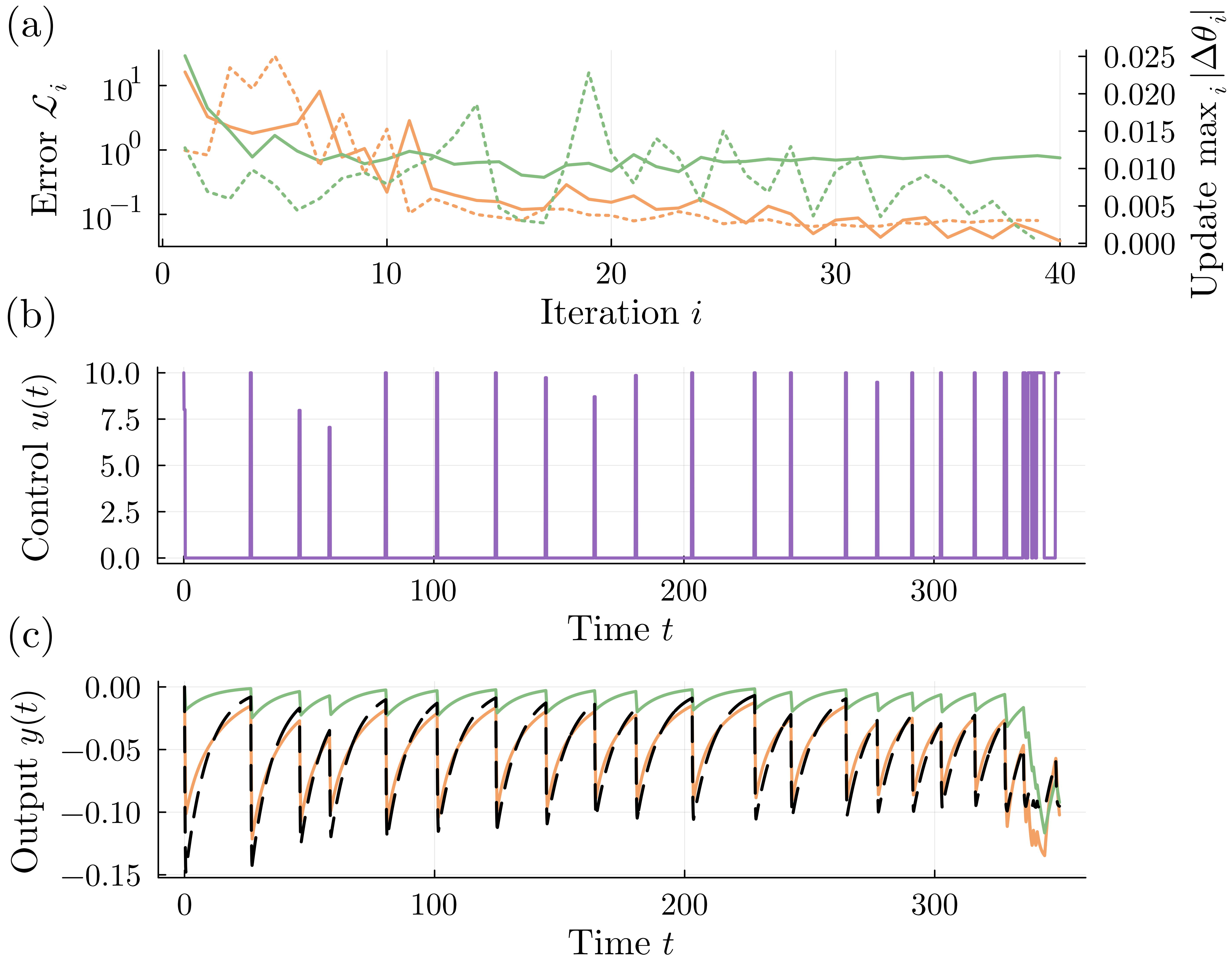
6-state model

$$\dot{x}_1 = \theta_1 u(t)\, x_6 - \theta_2 x_1\,,$$
$$\dot{x}_2 = \theta_2 x_1 + \theta_3 u(t)\, x_3 - \left[\theta_4 + \theta_5 u(t)\right] x_2\,,$$
$$\dot{x}_3 = \theta_6 x_4 + \theta_5 u(t)\, x_2 - \left[\theta_7 + \theta_3 u(t)\right] x_3\,,$$
$$\dot{x}_4 = \theta_8 u(t)\, x_5 - \theta_6 x_4\,,$$
$$\dot{x}_5 = \theta_7\, x_3 - \left[\theta_9 + \theta_8 u(t)\right] x_5\,,$$
$$x_6 = 1 - x_1 - x_2 - x_3 - x_4 - x_5\,,$$
$$y = \theta_{11}\, x_2 + \theta_{10}\, x_3\,.$$

Numerical Simulations

Candidate models:
3-state vs. 4-state

Reference system:
4-state



Numerical Simulations

Ref: 3-State	4-State	6-State
3-State	0.090(0.182) | 1.334(0.181)	0.432(0.736) | 3.393(3.465)
4-State	×	0.978(0.492) | 1.281(0.491)

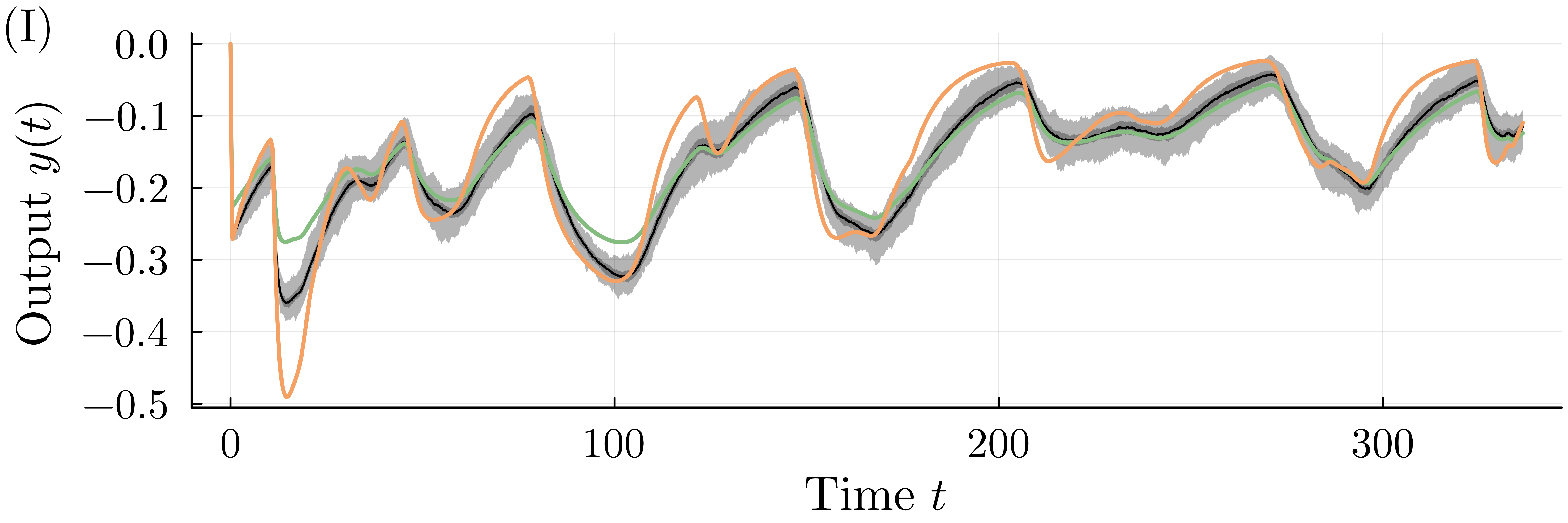
Ref: 4-State	4-State	6-State
3-State	0.320(0.176) | 0.228(0.118)	0.469(0.169) | 0.284(0.094)
4-State	×	0.230(0.193) | 1.044(2.463)

Ref: 6-State	4-State	6-State
3-State	0.571(0.338) | 0.226(0.132)	0.473(0.255) | 0.279(0.142)
4-State	×	0.725(1.287) | 0.718(1.414)

Numerical Simulations

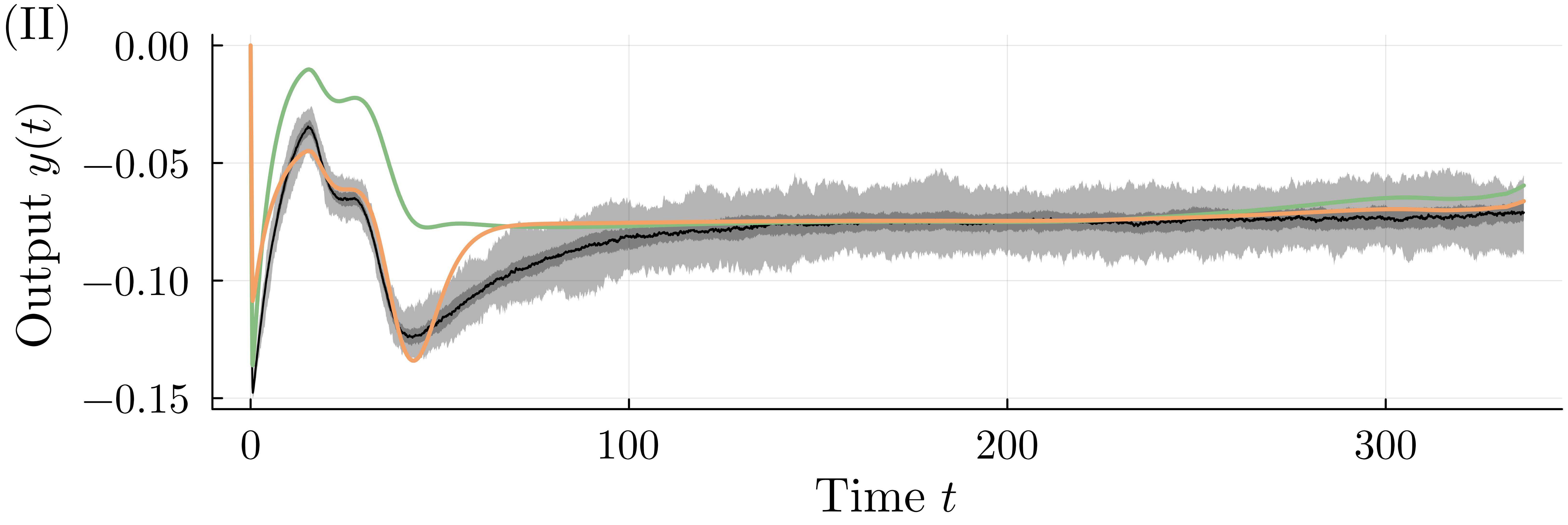
Candidate models:
3-state vs. 4-state

Reference system:
3-state

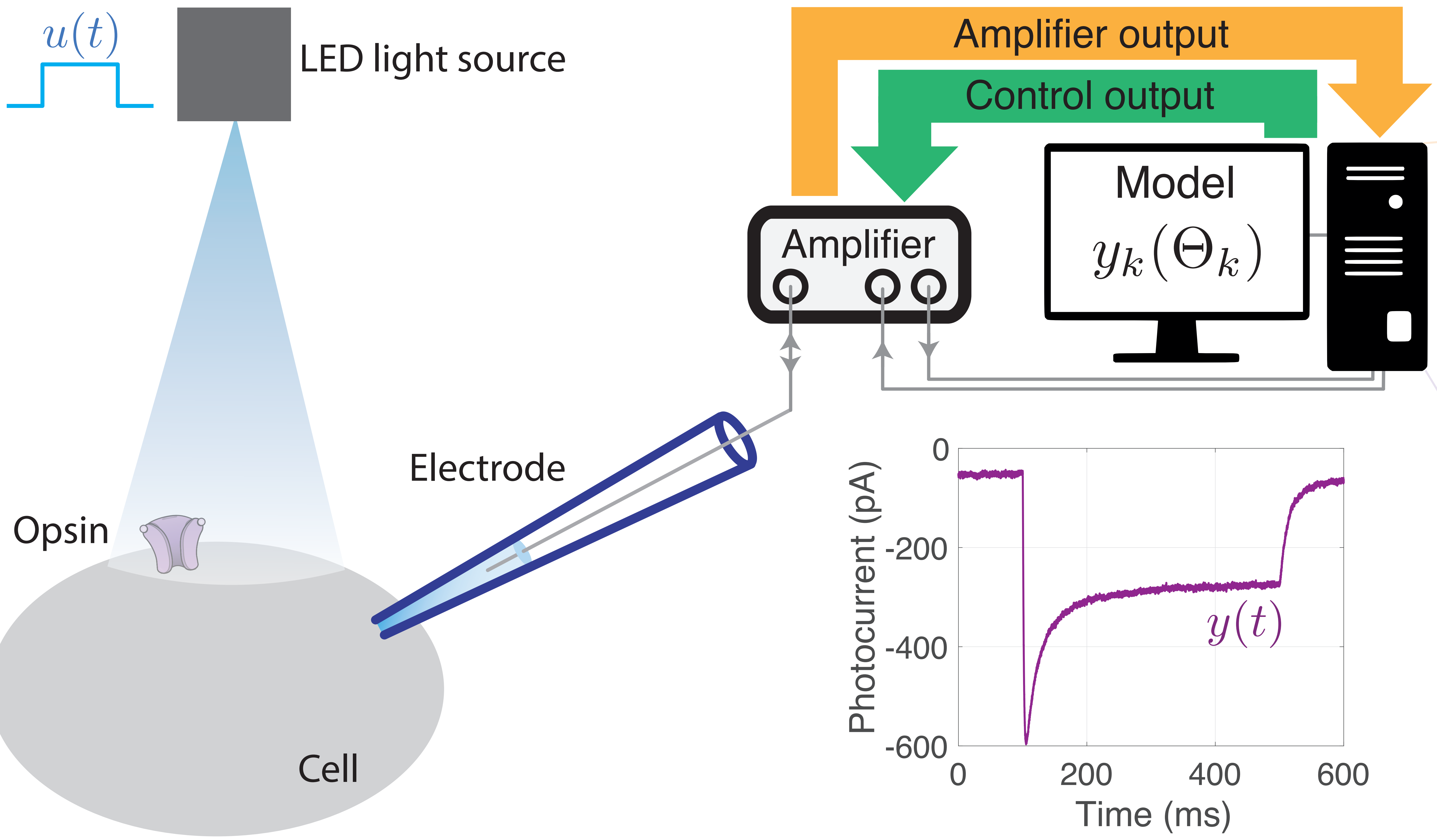


Candidate models:
3-state vs. 4-state

Reference system:
4-state



Computer — Experiment



Symphony is an OOP Matlab-based app for electrophysiology recording

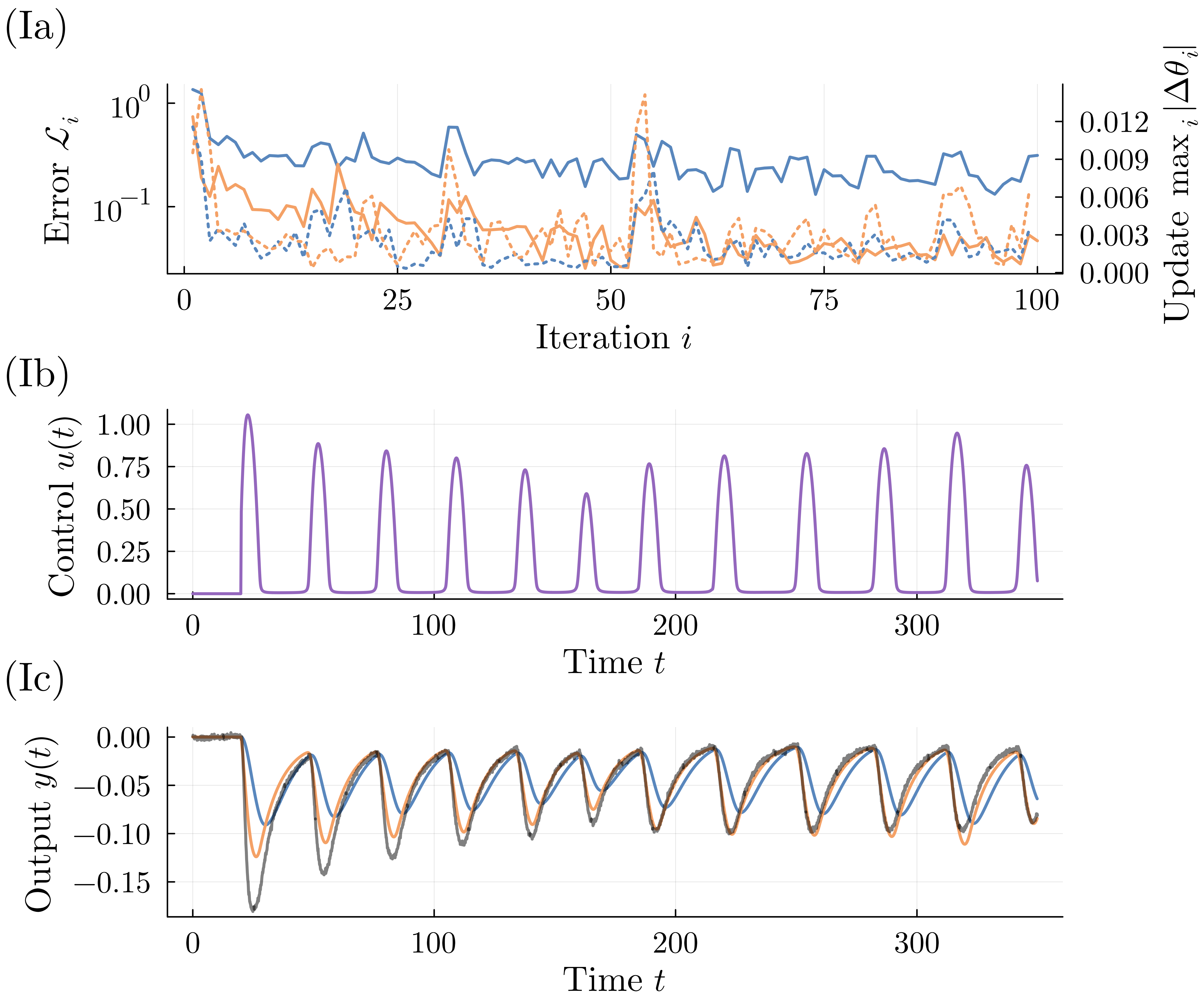
~10s

Sockets.jl to open *tcp server* to connect to following each data collection step

~5s

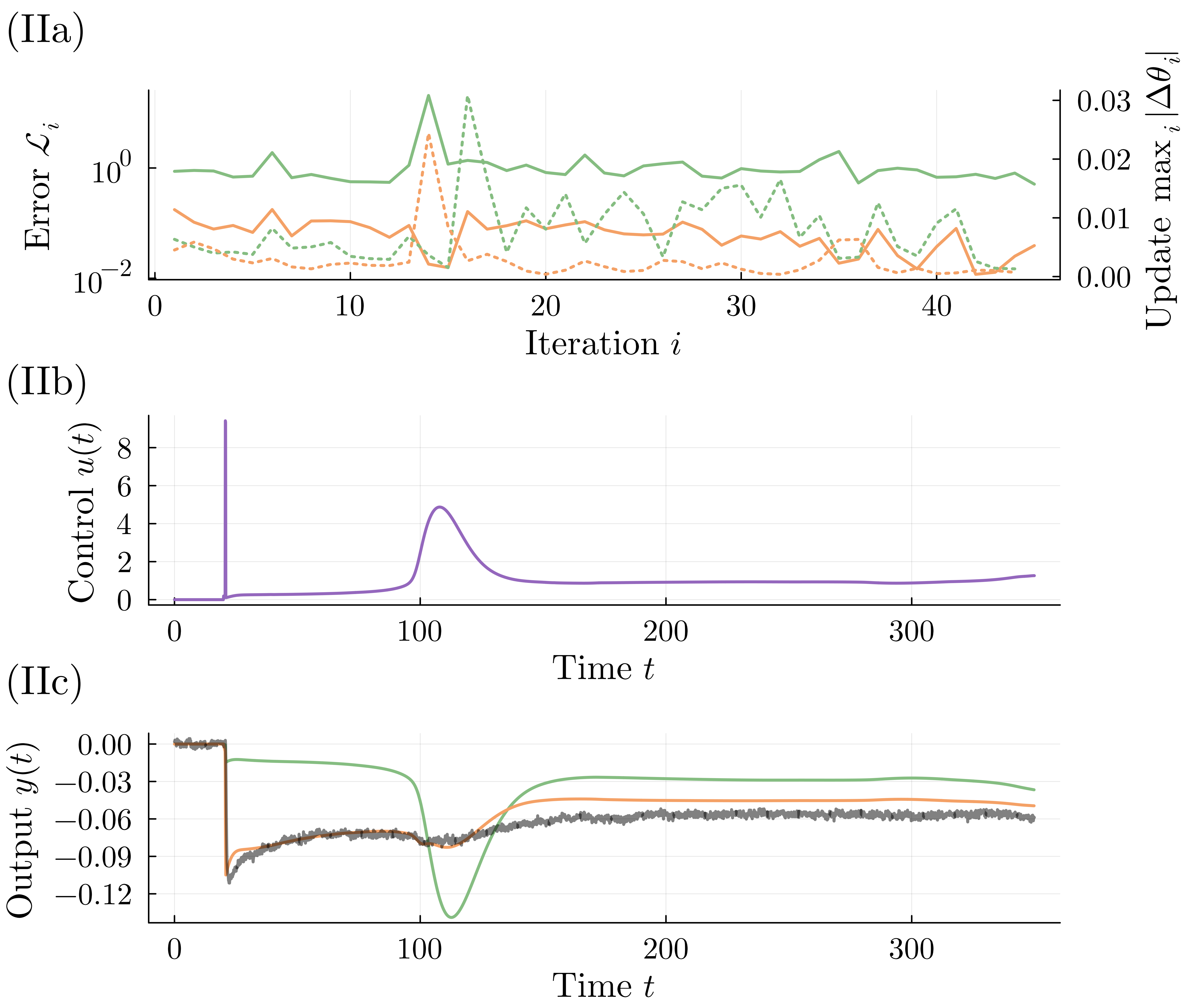
Experiment

Candidate models:
6-state vs. 4-state



Experiment

Candidate models:
3-state vs. 4-state



Conclusion

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- Closed-loop algorithm for model selection.
- Allowed to select the most accurate opsin model.
- Exploration of the phase space based on heuristics.

Future work

- Build digital twins.
- Leverage digital twin to optimize the control inputs.
- Apply to other systems.

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