

### Motivation

**Active filaments** are thin, elastic, slender rods that are commonly observed in nature. Driven by motor protein activity, active filaments play a crucial role in cellular processes such as **fluid transport**, **mixing**, and **swimming**, among many others.

Our goal is to analyse **filament dynamics in biological settings** using our numerical model, identify self-sustaining states (limit cycles), detect transitions between these states (bifurcations), and compute the stability of these states.

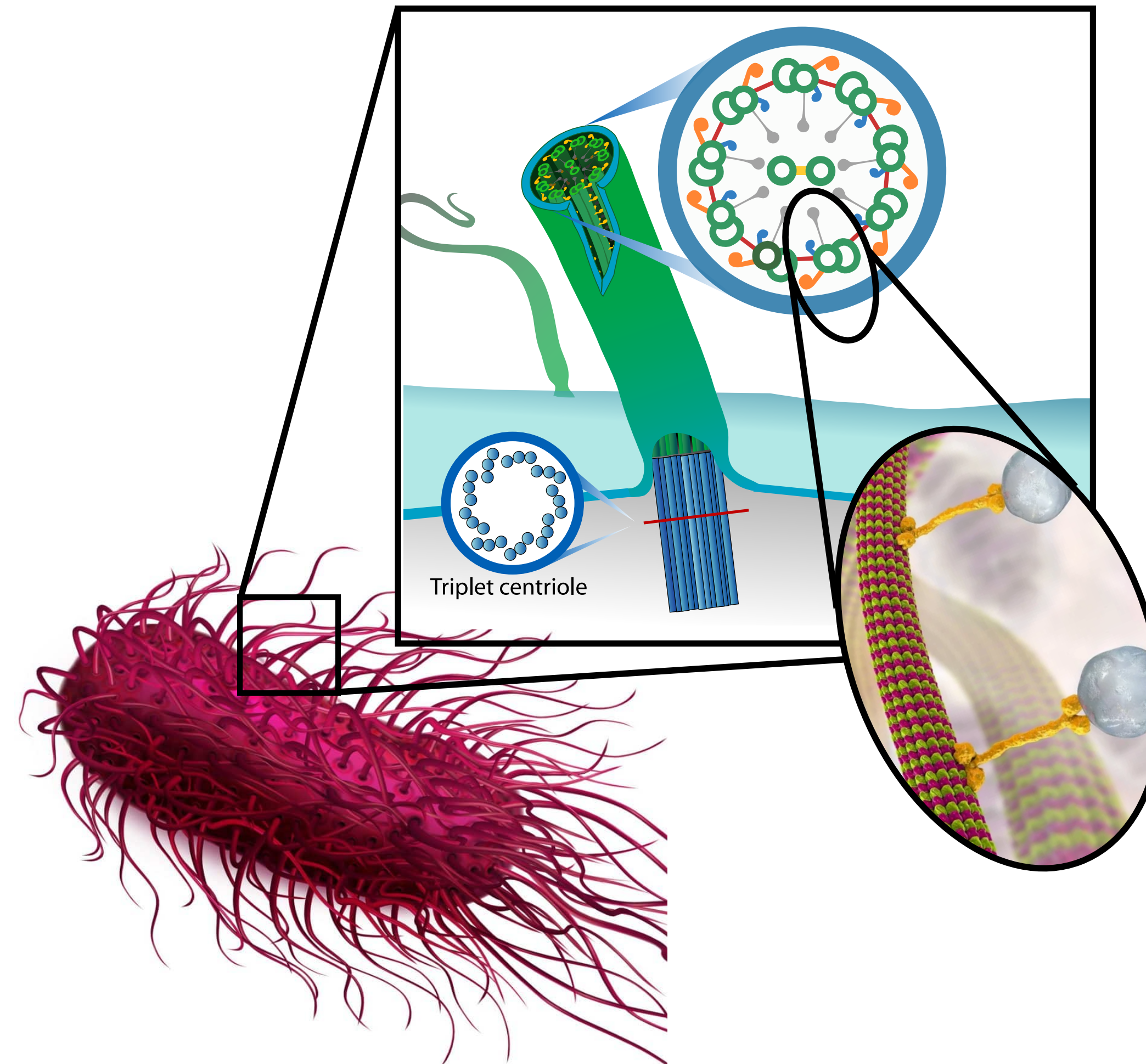


Figure 1: Illustration of a microfilament in a eukaryotic cell's flagella. Adapted from online illustrations of Mariana Ruiz Villarreal<sup>1</sup> and Kateryna Kon<sup>2</sup>.

### The Model and Methods

- Molecular motors exert compressive forces on the filament and create a slip-flow over filament surface.
- Discretise the filament into self-locomoting segments.
- Solve the equations in the Stokes limit<sup>1</sup>: velocity and forces are linearly related!
- Model the squirming effect (effect of motor proteins) as a nonlinear forcing and solve for the velocity using Faxén's Laws.<sup>2</sup>

$$\begin{bmatrix} V \\ \Omega \end{bmatrix} = \mathcal{M}^{\text{RPY}} \begin{bmatrix} \mathbf{F}^H \\ \mathbf{T}^H \end{bmatrix} + \mathcal{M}^{\text{sq}} \begin{bmatrix} \mathbf{H}(b_1) \\ 0 \end{bmatrix}$$

- $b_1$  measures **motor protein activity**.
- Analyse recurrent patterns in the dynamics using Poincaré maps.
- Use a Jacobian-free Newton-Krylov (JFNK) method to obtain accurate representations of periodic states and compute their Floquet stability.
- Track each solution branch to find the bifurcations.

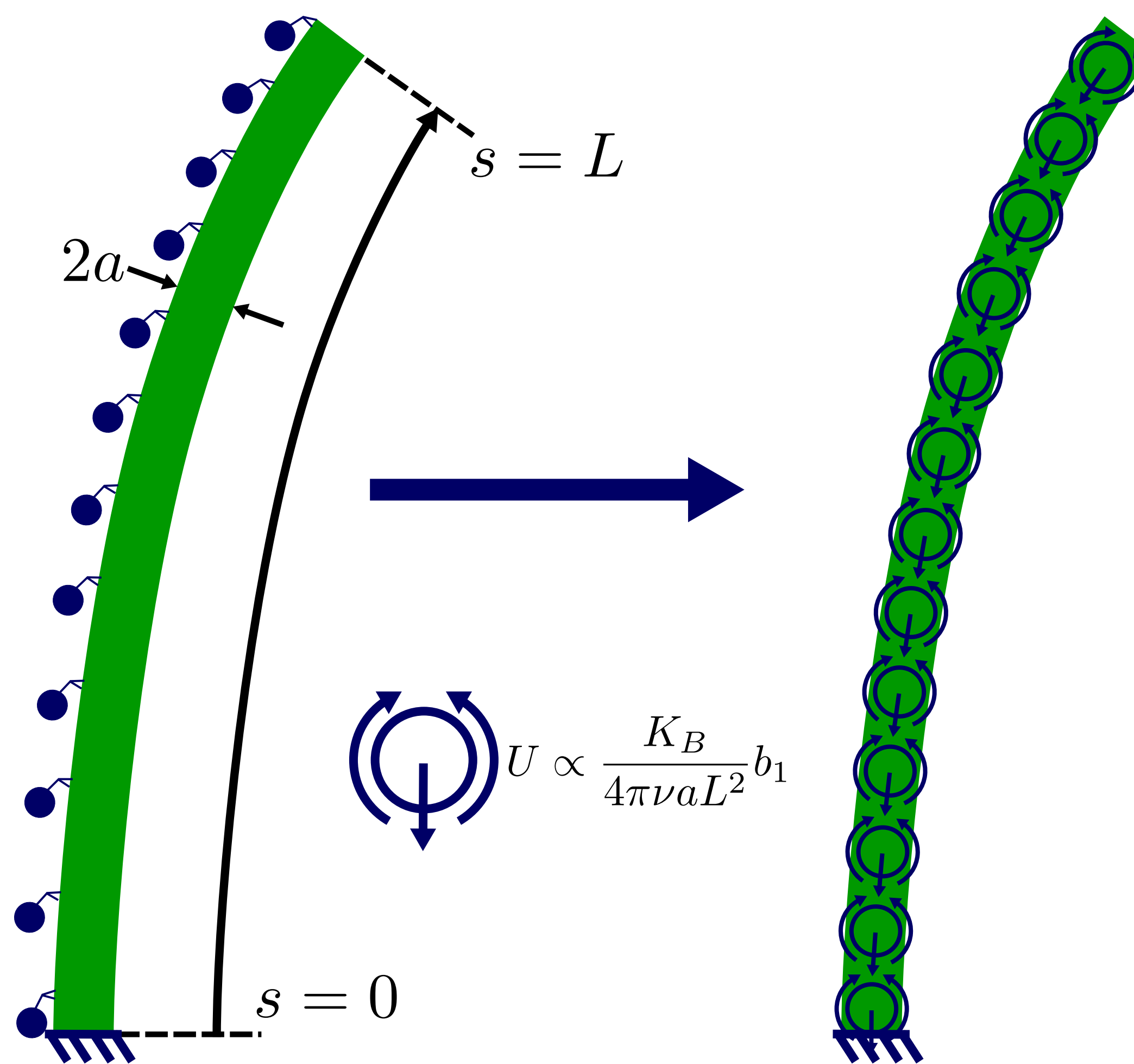


Figure 2: Schematic of the modelling approach employed to describe the motor protein activity and resulting filament dynamics numerically. The filament is discretised into self-locomoting squirmers.  $a$  is the radius of the filament's cross-section,  $L$  is the length of the filament,  $K_B$  is filament stiffness, and  $\nu$  is fluid viscosity.

Table 1: Bifurcations of the squirming filament, with  $b_1$  values given in the bottom row. DH: double Hopf bifurcation, PB: pitchfork bifurcation, HB: Hopf bifurcation.

Event	DH	PB	HB1	HB2
$b_1$	19.1	80.8	90.8	184

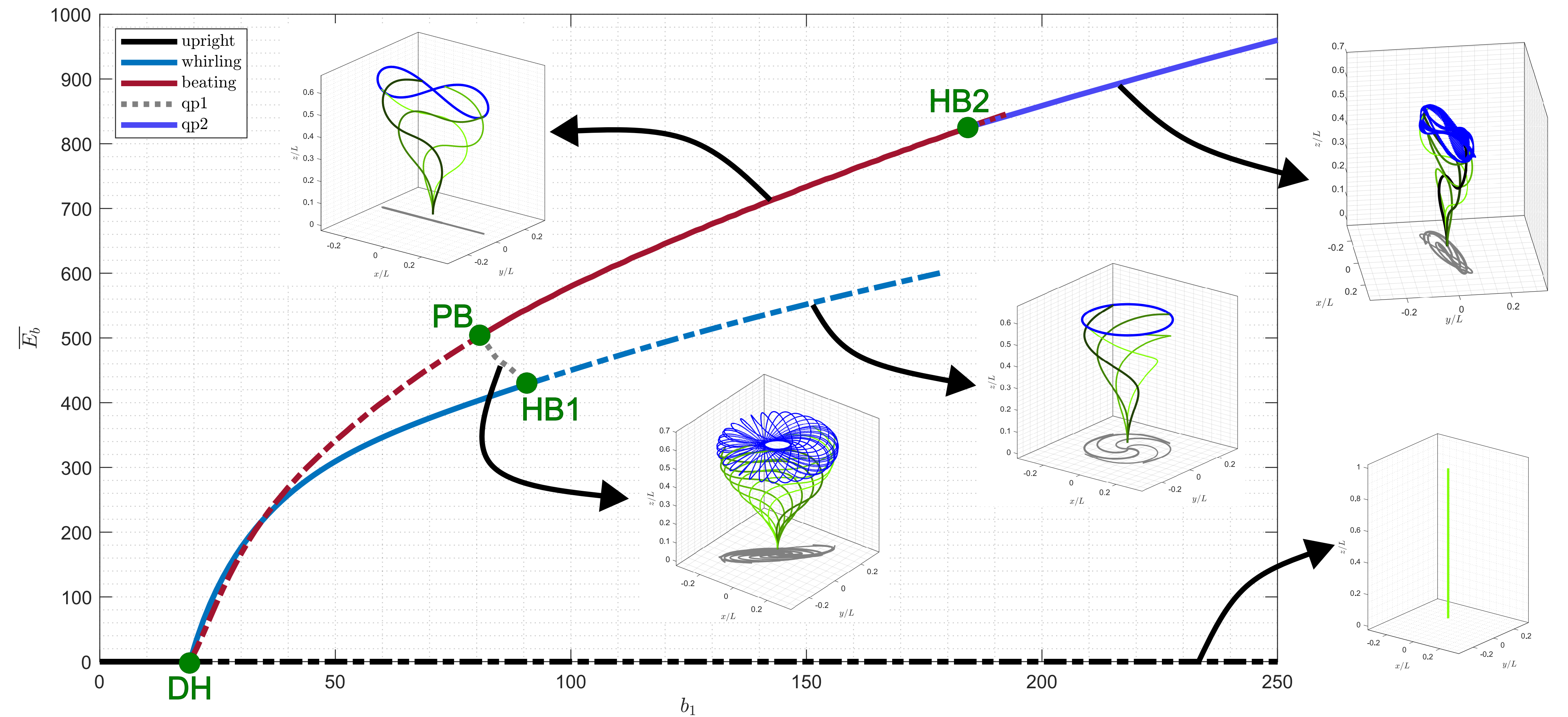


Figure 3: Bifurcation diagram for the squirming filament, average bending energy ( $\bar{E}_b$ ) vs. motor protein activity ( $b_1$ ). Upright is a steady state. Whirling and beating are periodic states. QP1 is unstable and carries the characteristics of both whirling and beating. QP2 is stable and describes a coiled filament state with changing handedness. DH: double Hopf bifurcation, PB: pitchfork bifurcation, HB: Hopf bifurcation.

### Results

We identify five distinct states: **upright**, **whirling**, **beating**, **QP1**, and **QP2**. Upright is steady; whirling and beating are periodic orbits; QP1 and QP2 are quasi-periodic states.

- **Double Hopf** bifurcation: a dynamic instability with two distinct eigenmodes. The **phase difference** between the modes determines the state: beating ( $\Delta\phi = 0$ ), and whirling ( $\Delta\phi = \frac{\pi}{2}$ ).
- **Bistability** of whirling and beating in the range  $b_1 \in [80.8, 90.8]$ .
- **Modal decomposition** of QP1 into whirling and beating:  $\mathbf{u}_{QP1}(t) \approx c_W \mathbf{u}_W(t) + c_B \mathbf{u}_B(t + \phi)$ , displaying both characteristics.
- At high actuation, transition to QP2 – a **coiled filament with changing winding direction**.
- **Robust dynamics** to changes in motor protein activity  $b_1$ . QP2 does not transition to chaos!

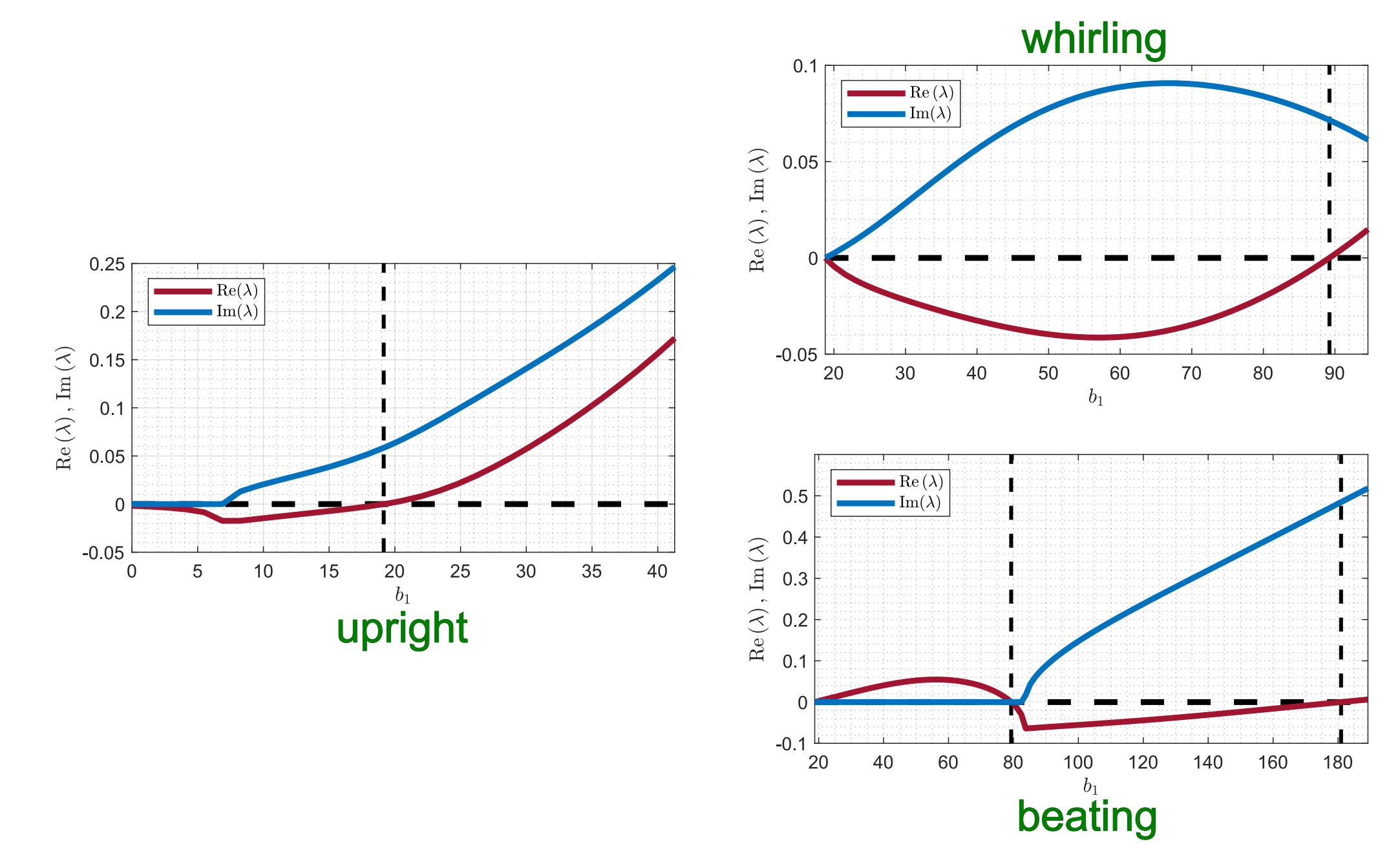


Figure 4: Linear stability analysis of the upright, whirling, and beating states: instability growth rate ( $\lambda$ ) vs. motor protein activity ( $b_1$ ).

### Future Work

- **Data-driven analysis** of the dynamics to explain the hydrodynamic interactions leading to the observed filament behaviours.
- Extending the current framework to investigate **collective dynamics** of multiple filaments.

### Affiliations

\* Department of Mathematics, \*\* Department of Aeronautics, Imperial College London

### References

<sup>1</sup>Schoeller et al. JCP, 2020. <sup>2</sup>Clarke, B. PhD Thesis. <sup>3</sup><http://ladyofhats.com/> <sup>4</sup><https://www.sciencephoto.com/>