

Steering Chiral Swimmers

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Life at low Reynolds number

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J. Pecreaux
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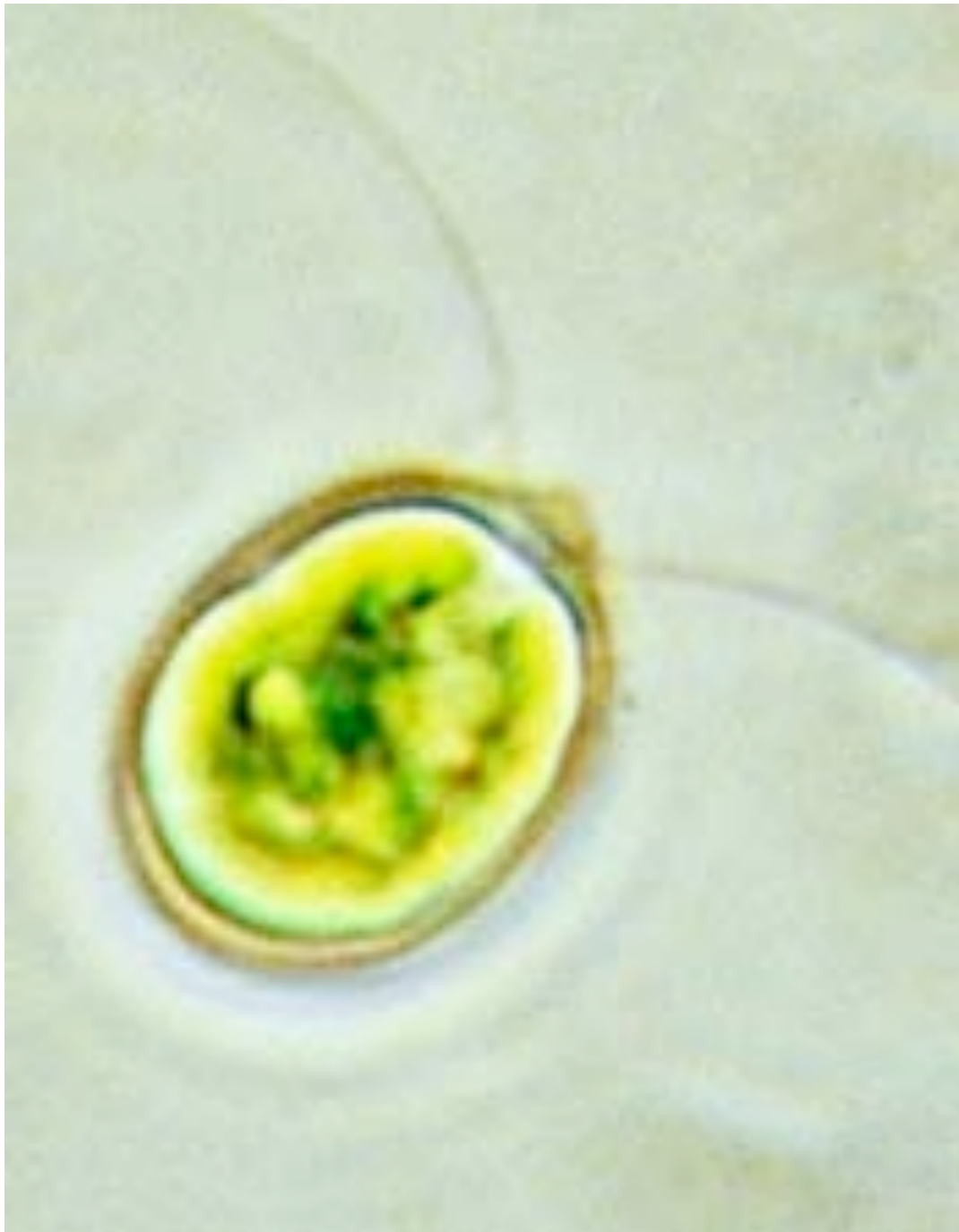
U.B. Kaupp (Bonn)

J. Prost (Paris)
J.-F. Joanny (Paris)

A. Vilfan (Ljubljana)

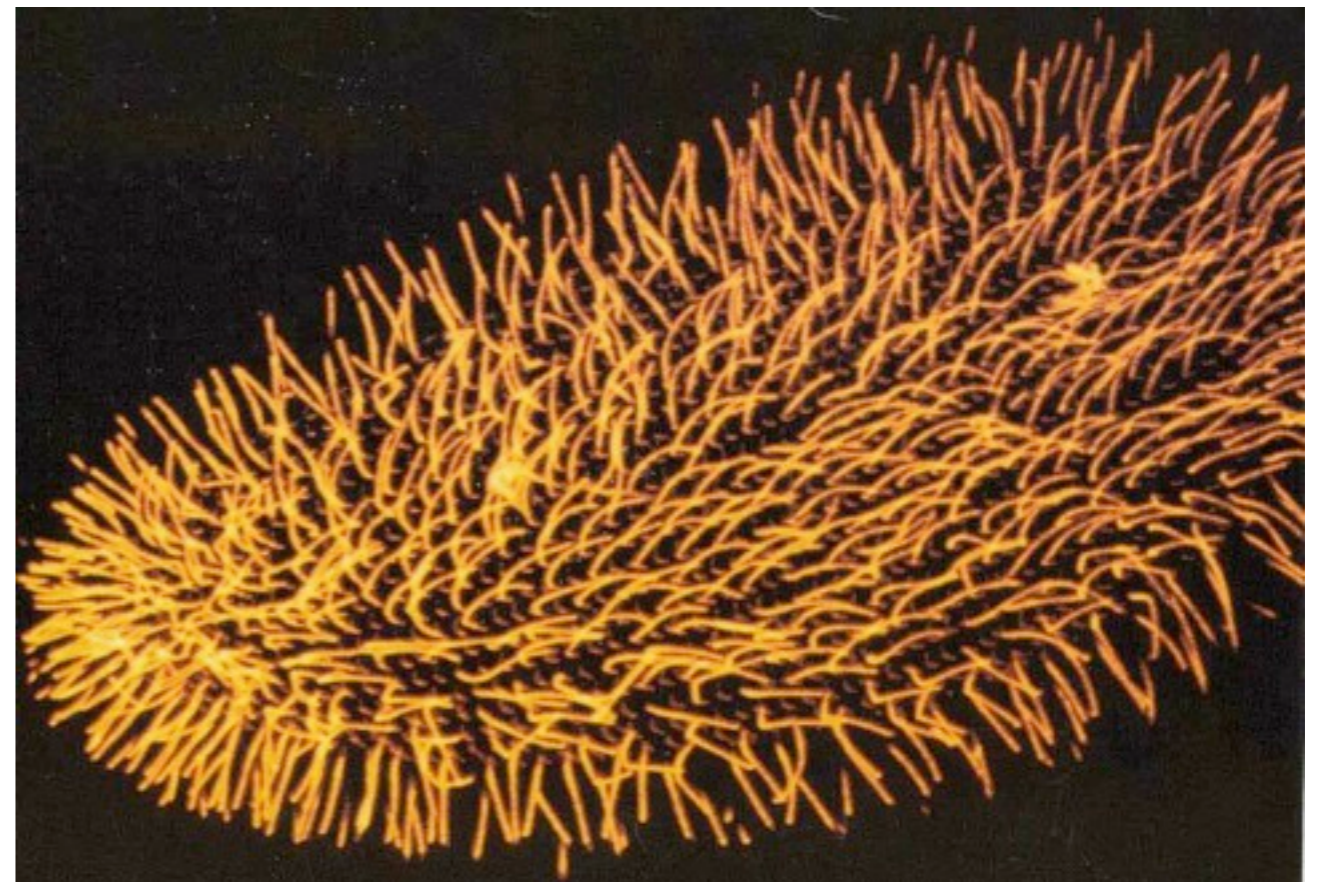
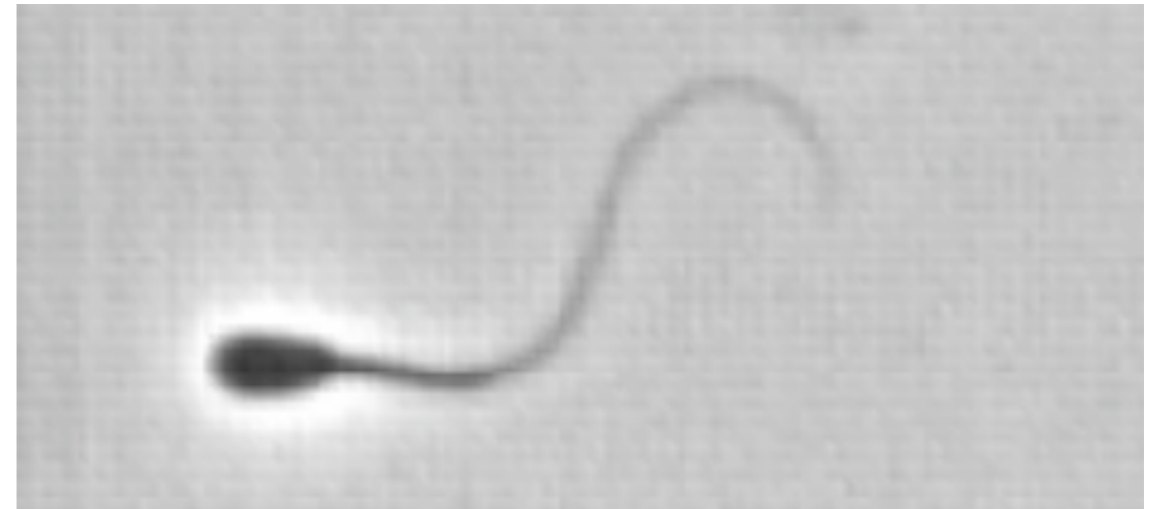
Ciliar motility

Swimming of cells



Chlamydomonas

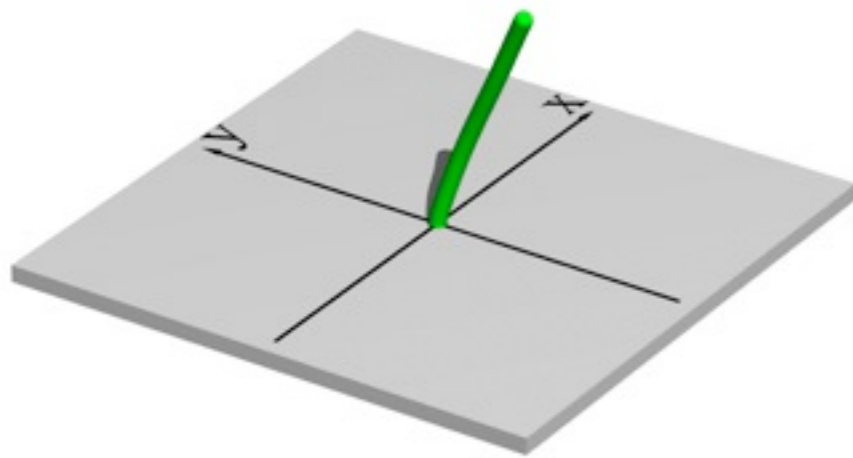
Sperm



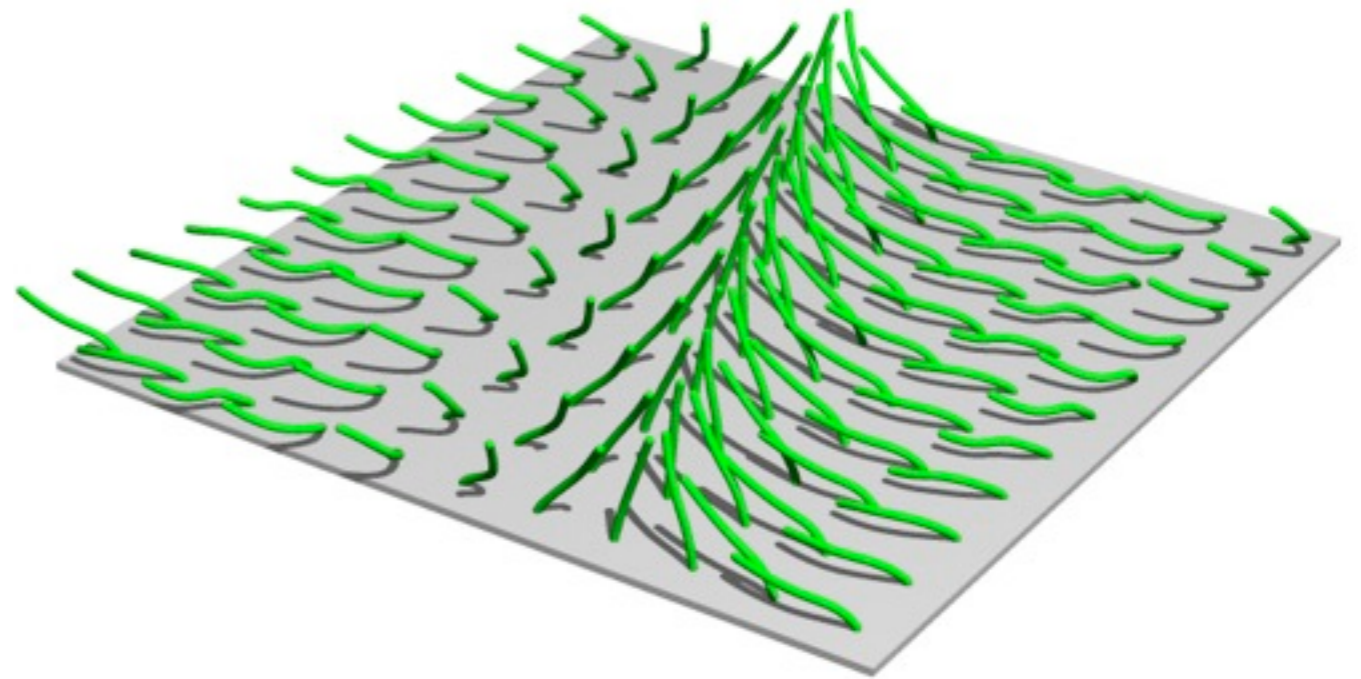
Paramecium

Ciliar motility

Stirring fluids



Ciliar stroke



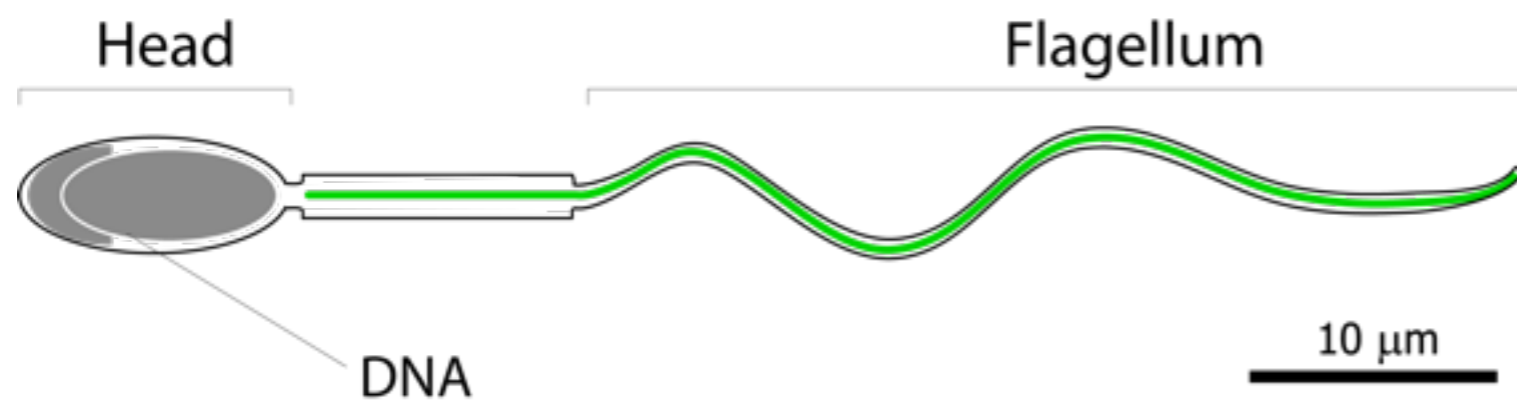
Metachronal waves

Swimming



Bull sperm

20Hz

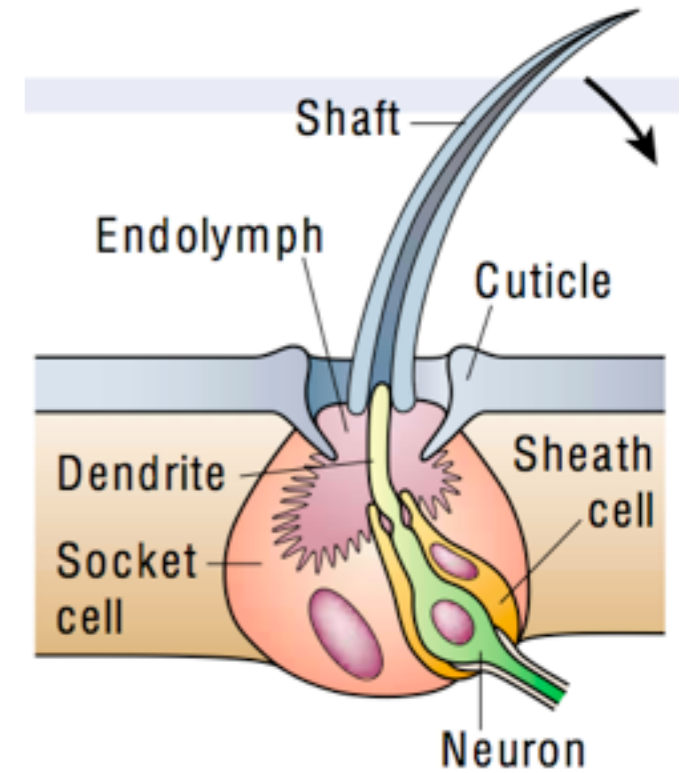


Ingmar Riedel-Kruse
Jonathon Howard

Cilia as sensory elements

Mechanosensors

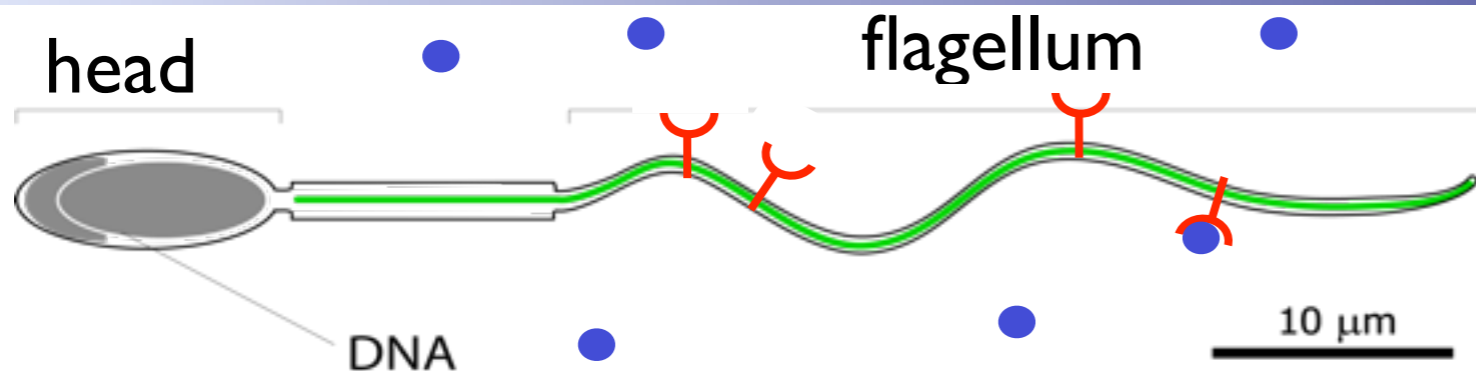
Insect mechanosensors



Chemosensors

Olfactory neurons

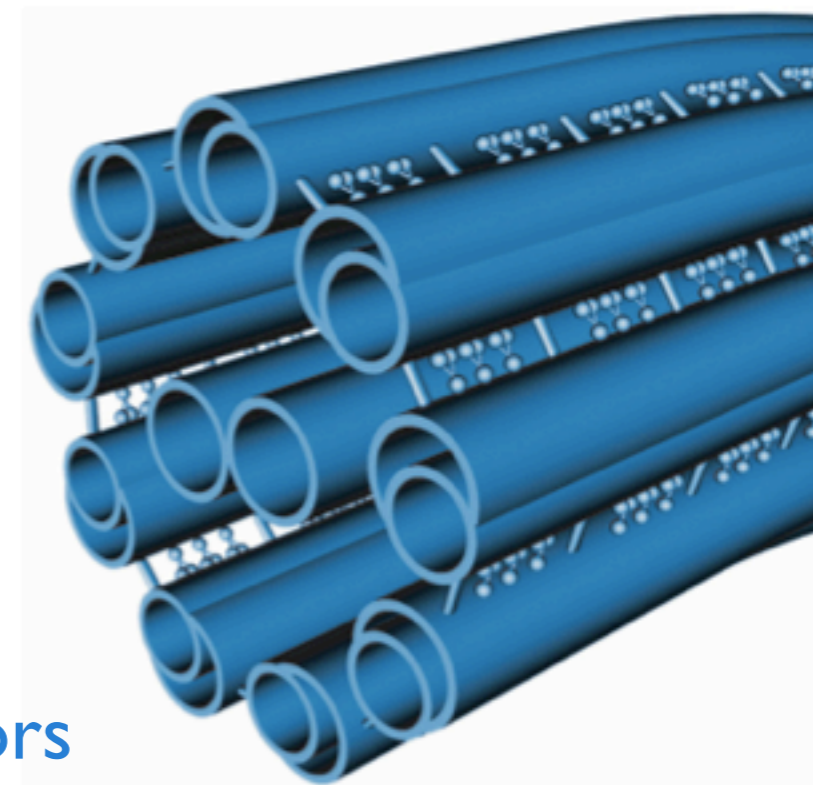
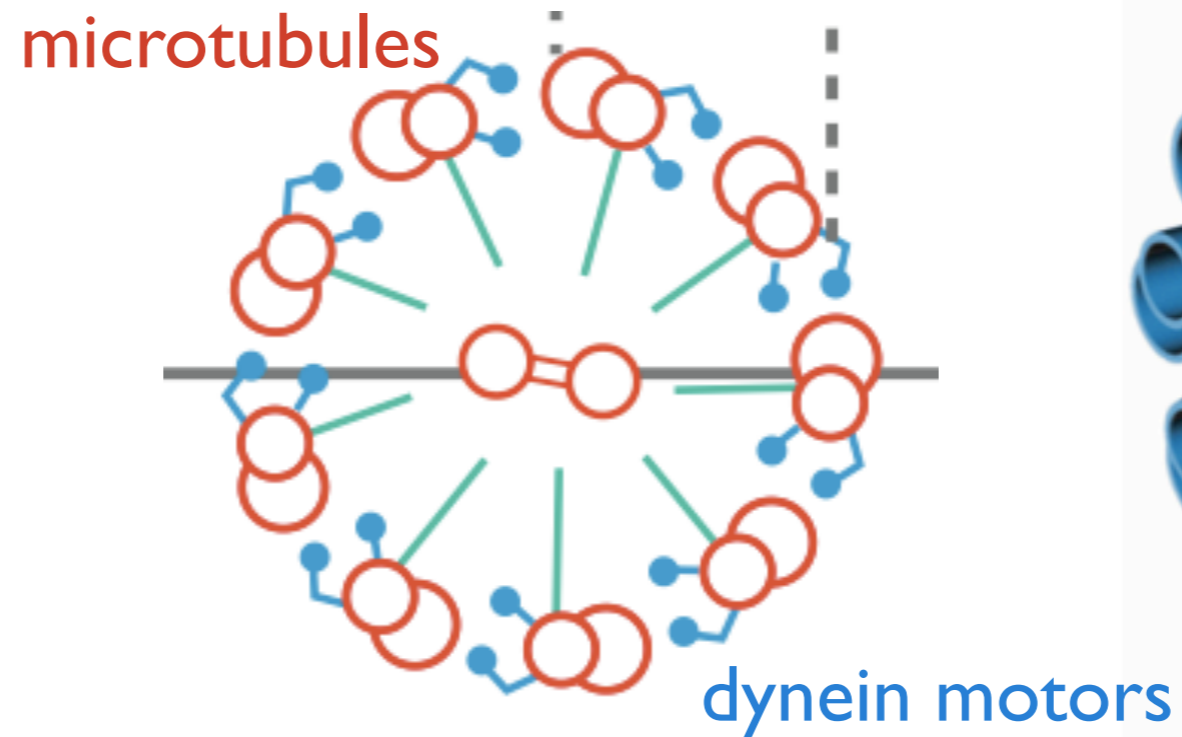
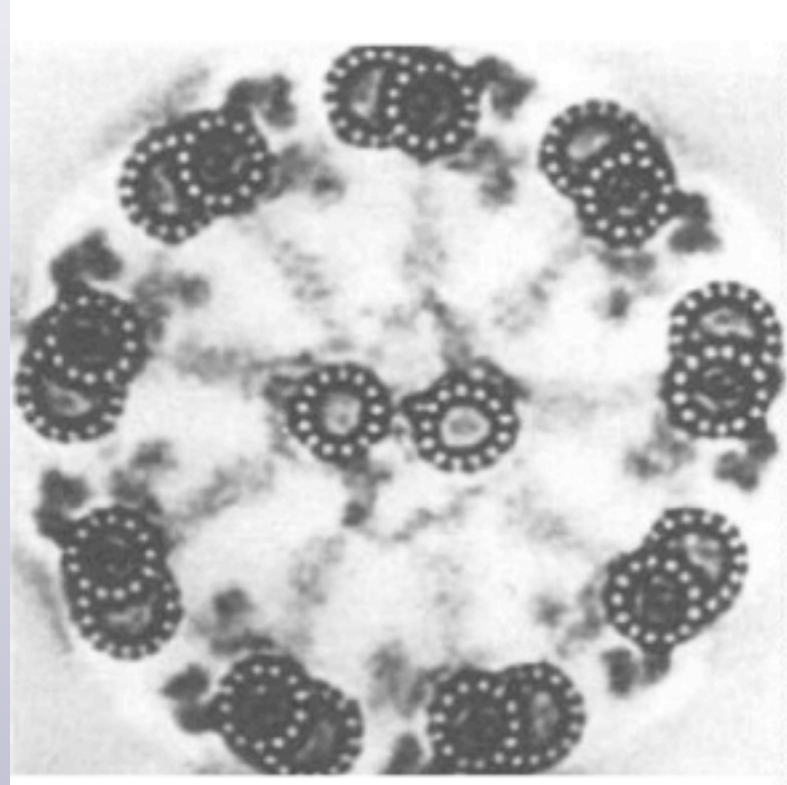
Sperm chemotaxis



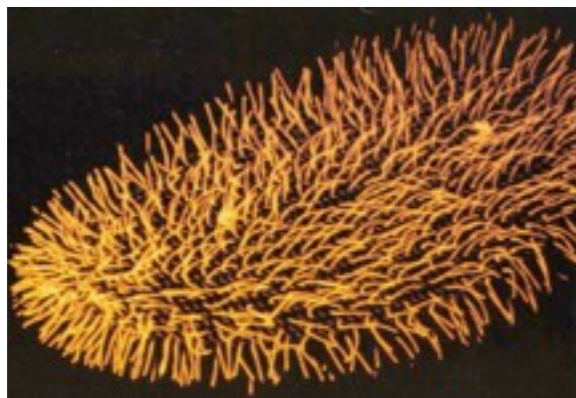
Y receptor
● chemoattractant

Ciliar structure: the axoneme

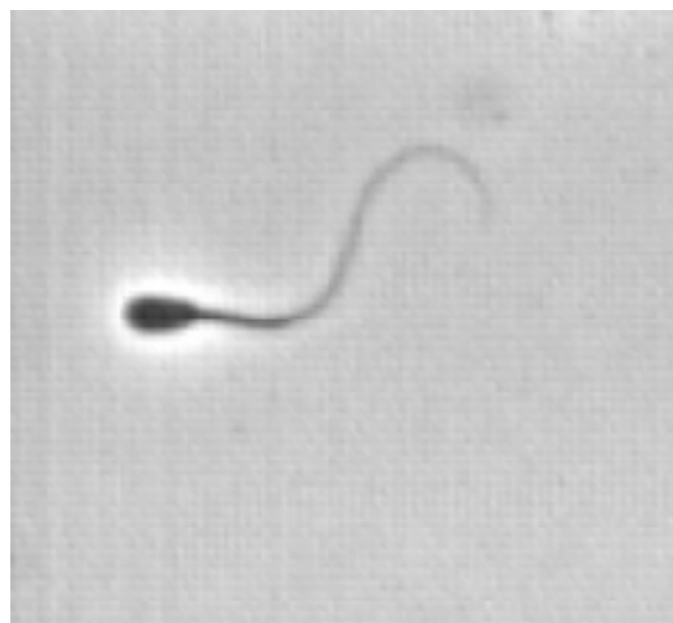
9+2 Axoneme



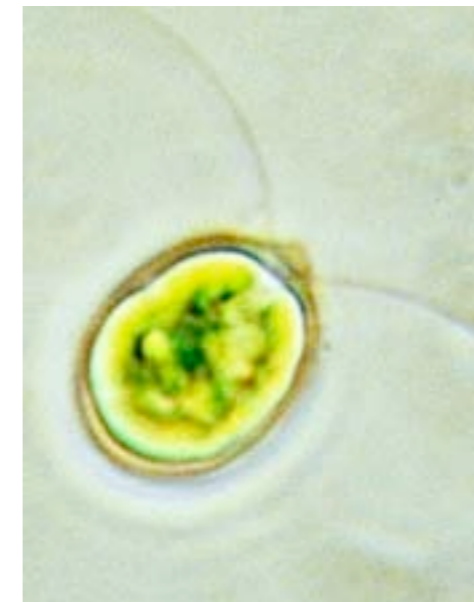
Paramecium



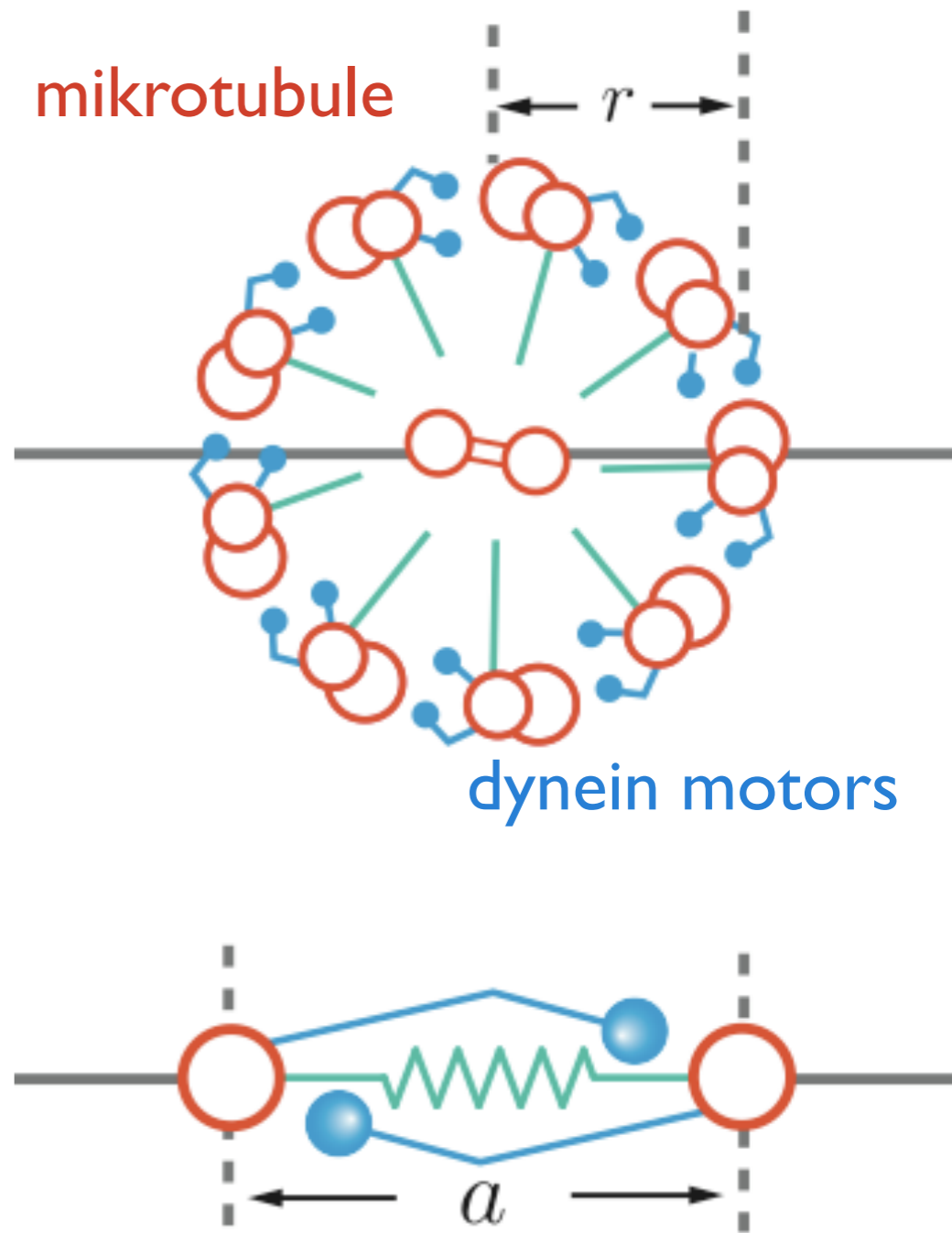
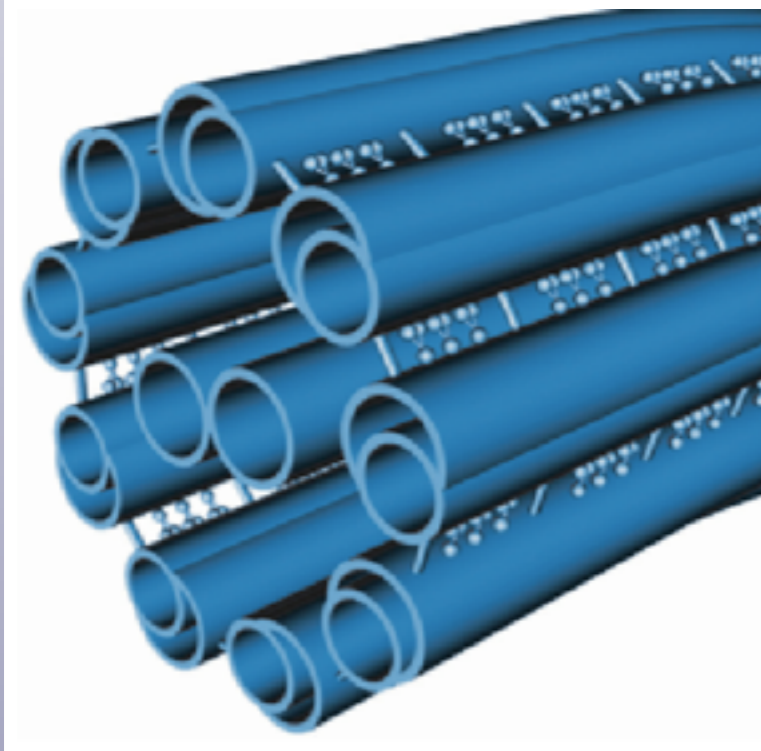
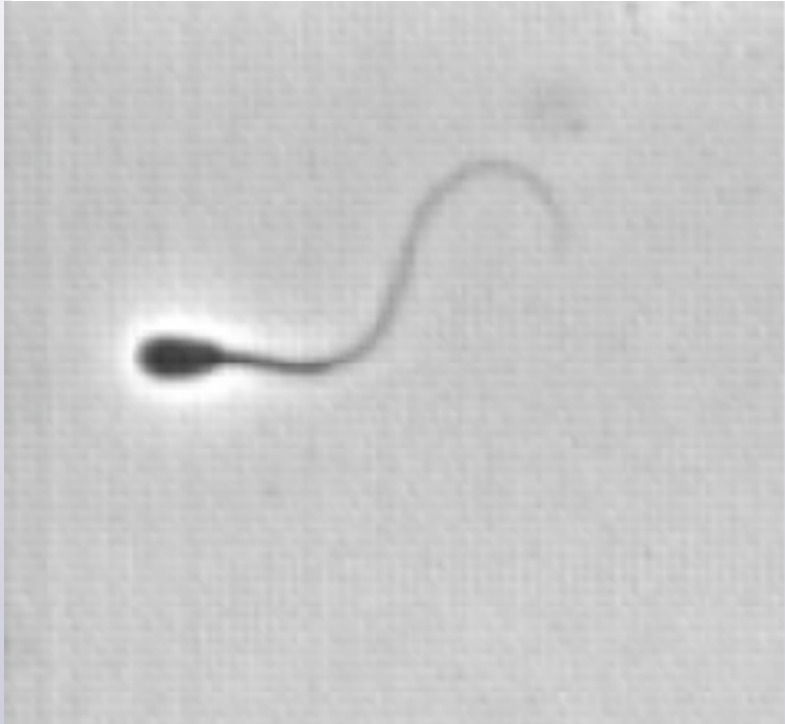
Sperm



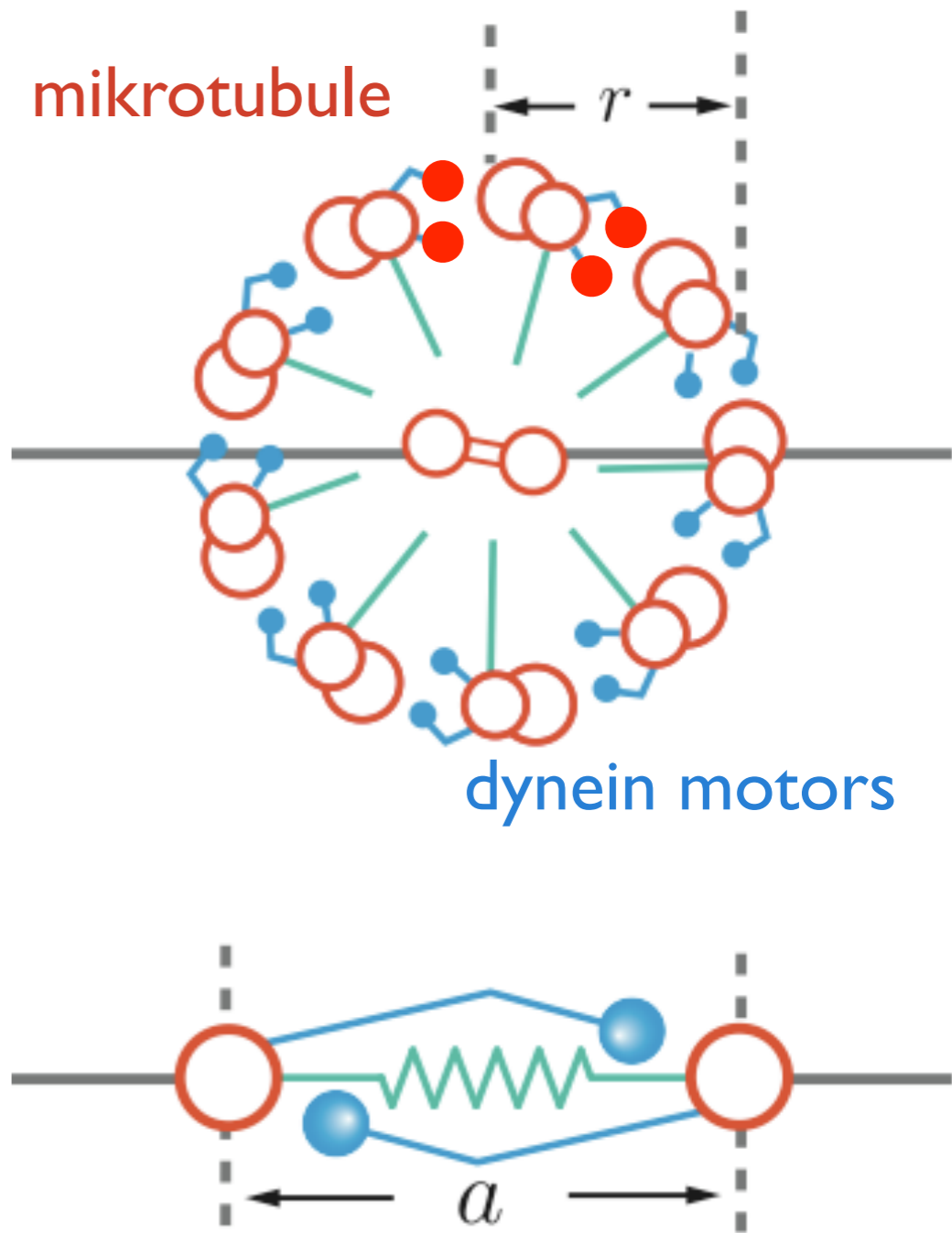
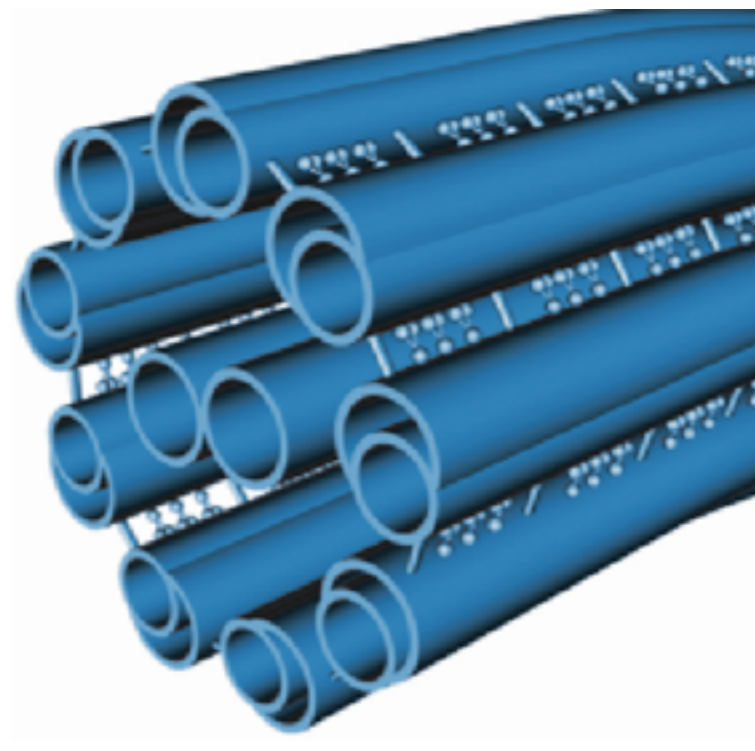
Chlamydomonas



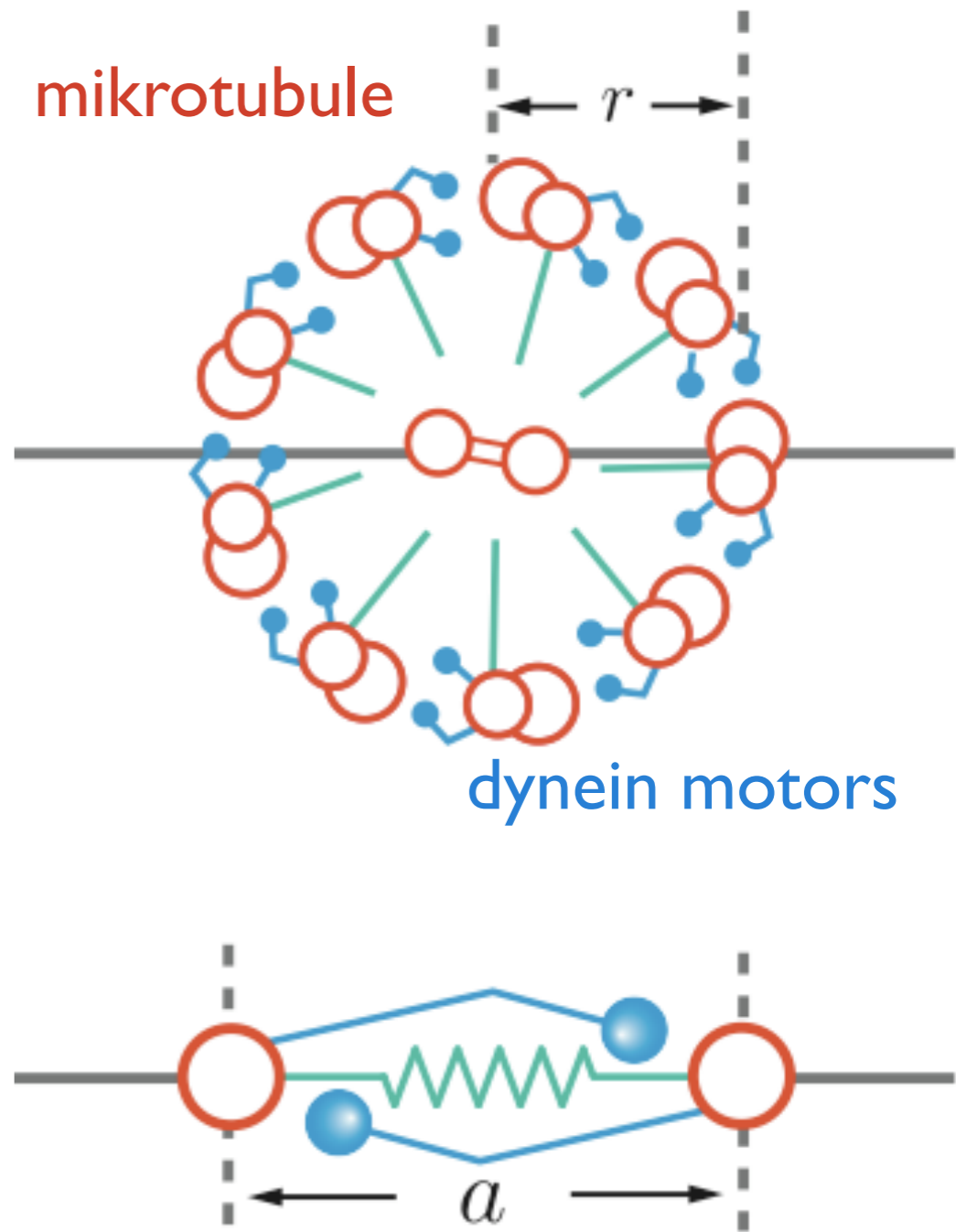
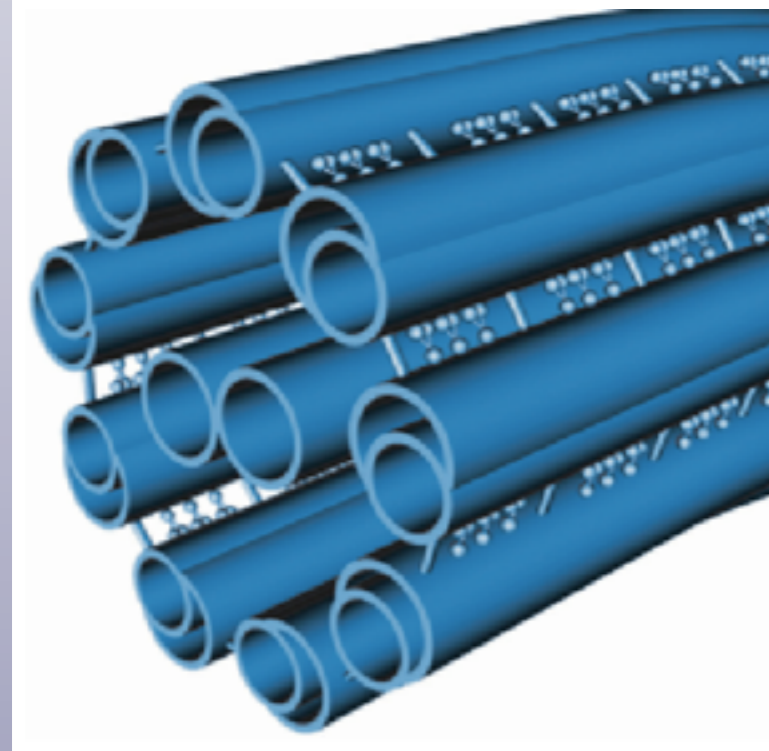
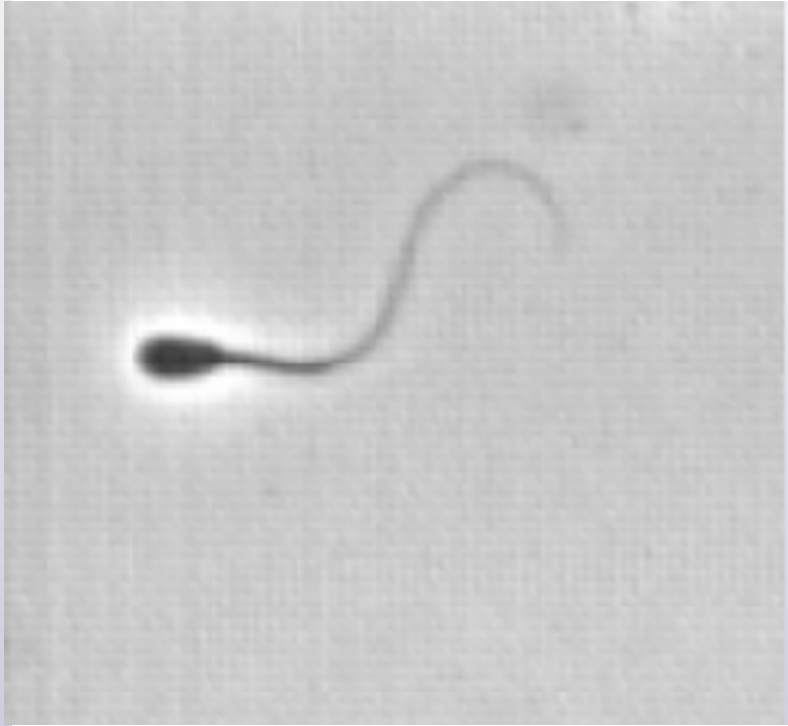
Planar ciliar beat



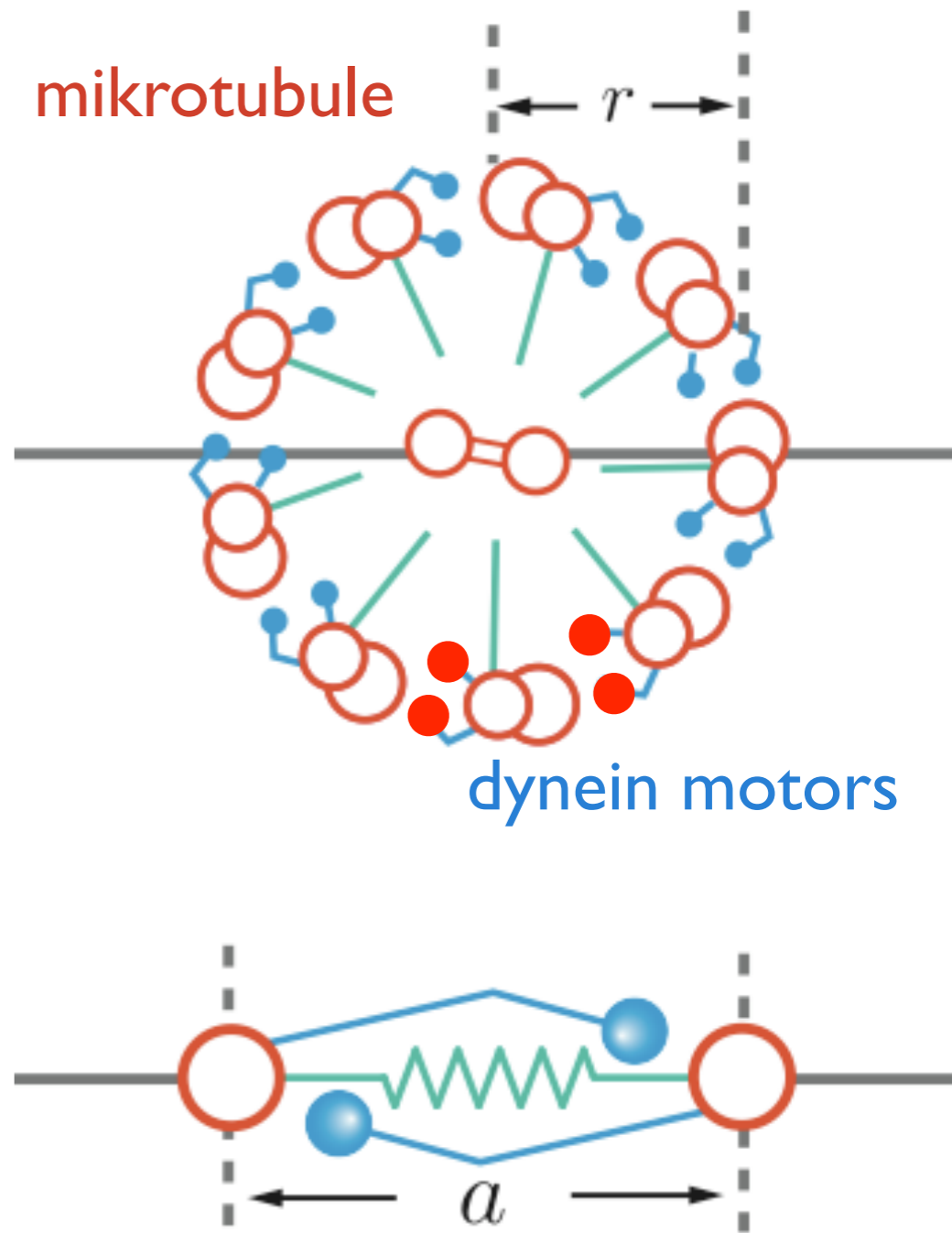
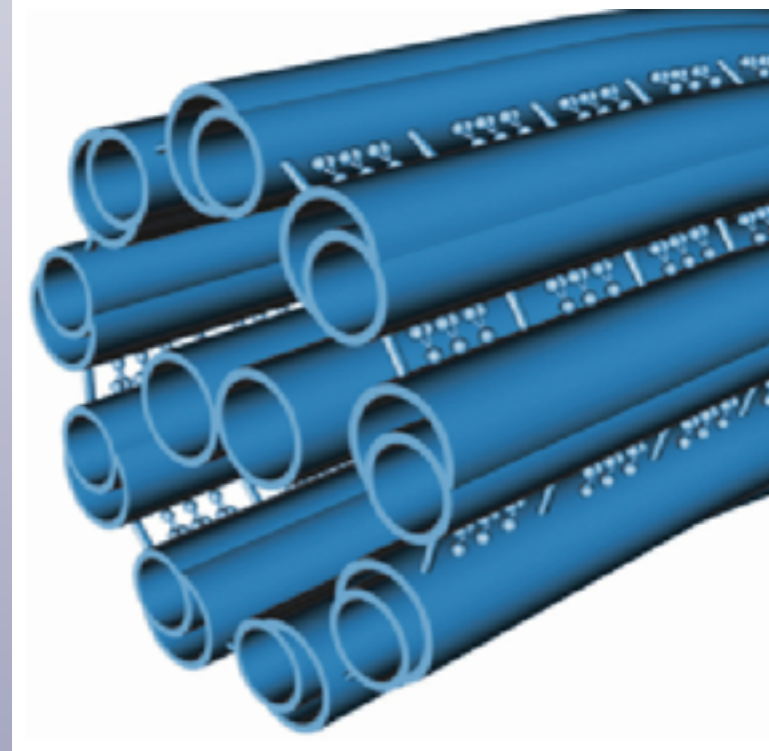
Planar ciliar beat



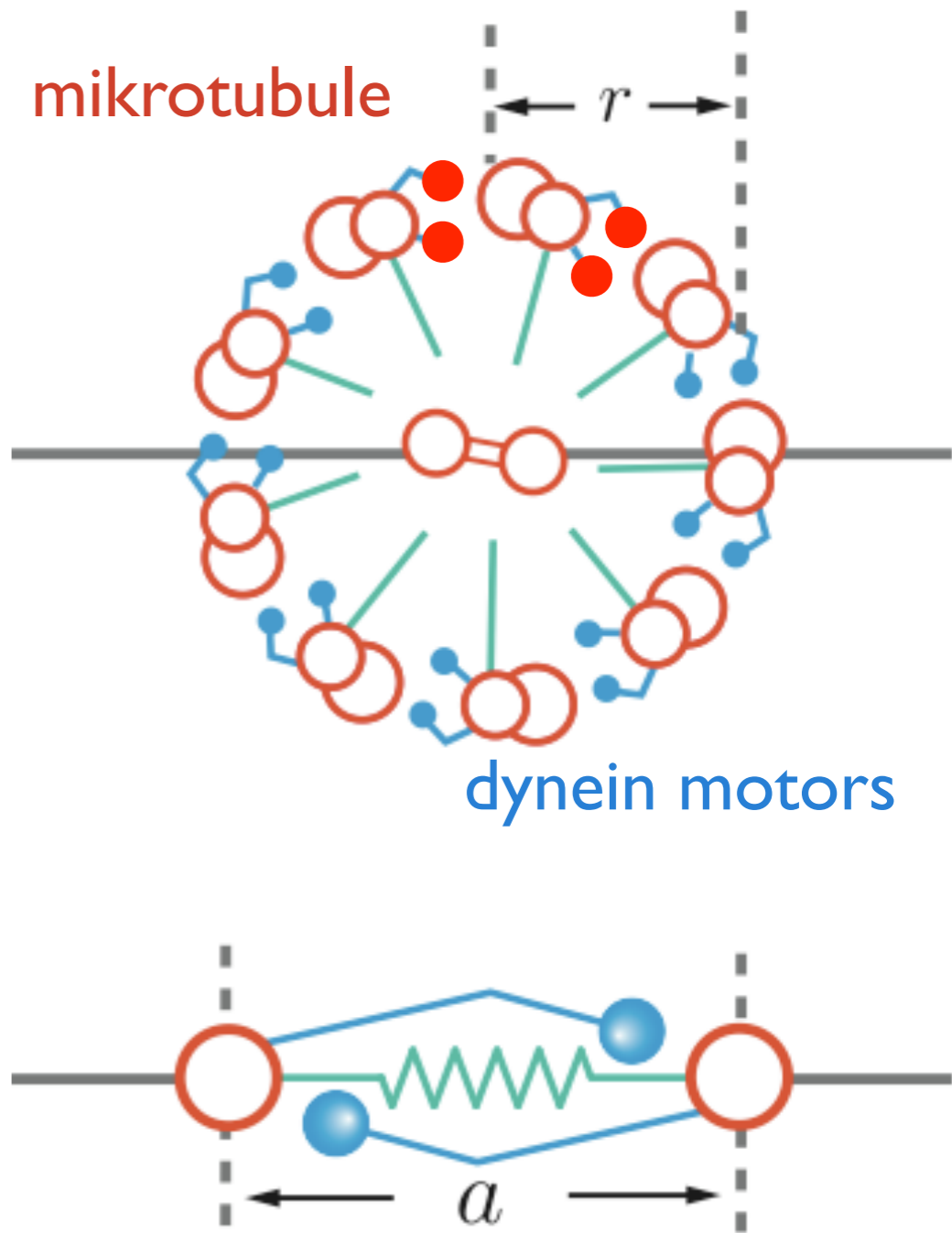
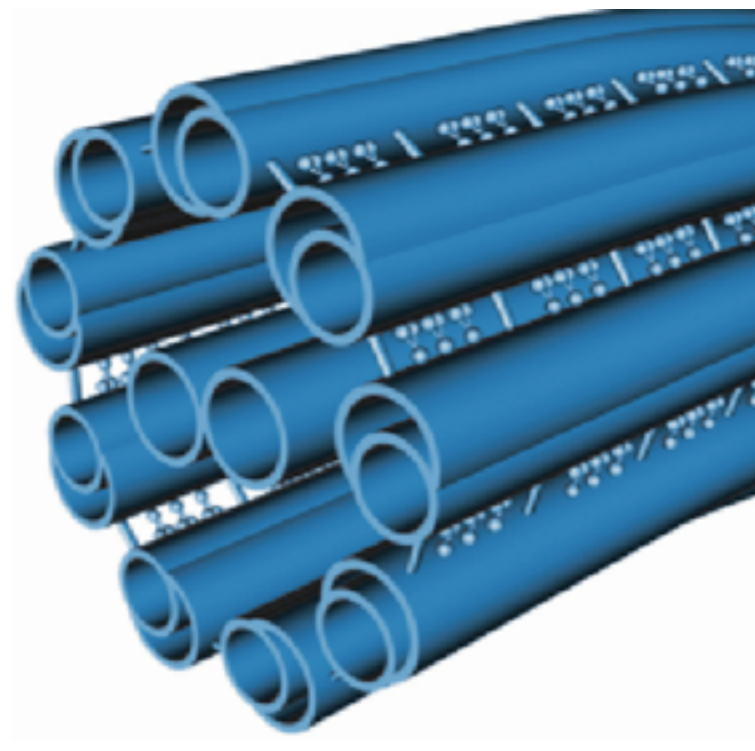
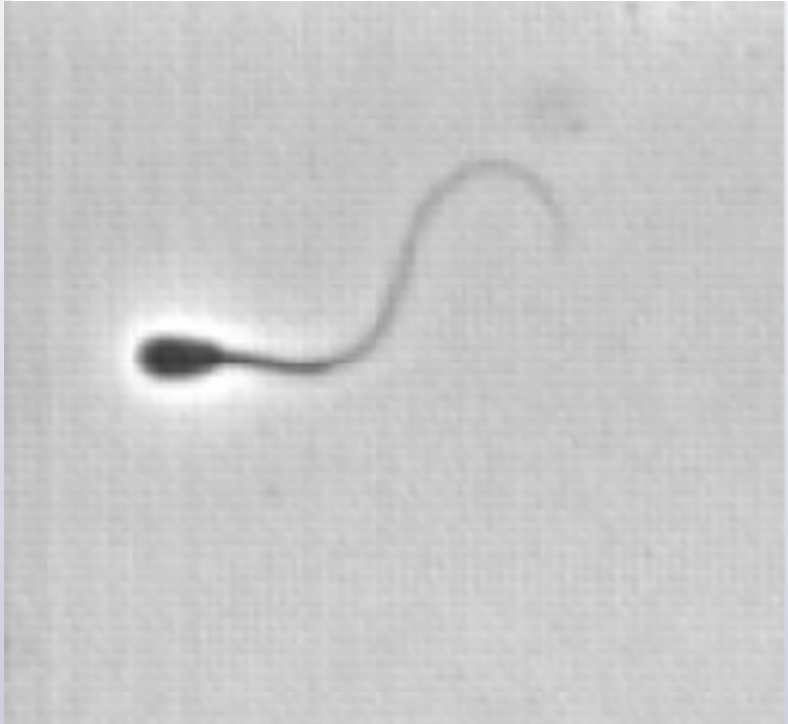
Planar ciliar beat



Planar ciliar beat

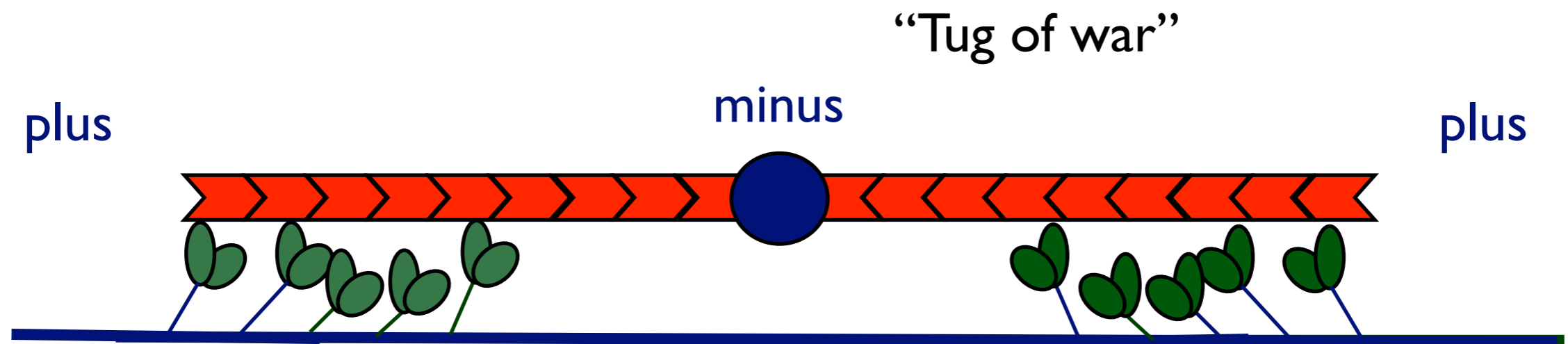


Planar ciliar beat



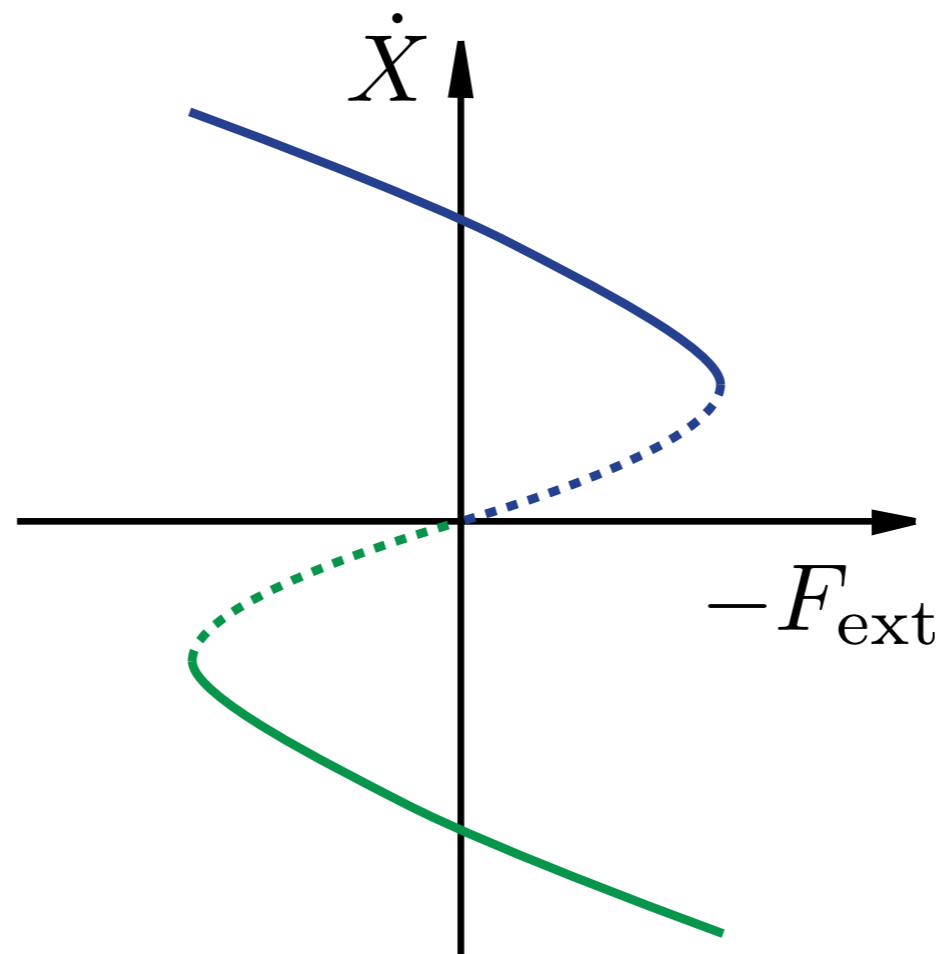
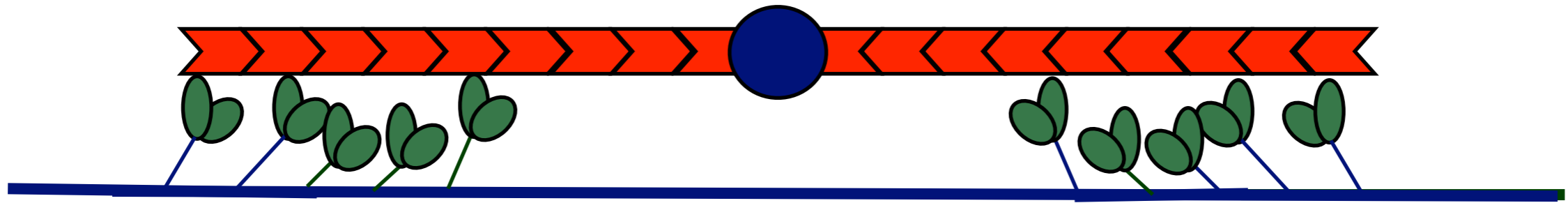
Antagonistic motors

Two groups of motors that act in opposition



Enhanced collective effects and instabilities

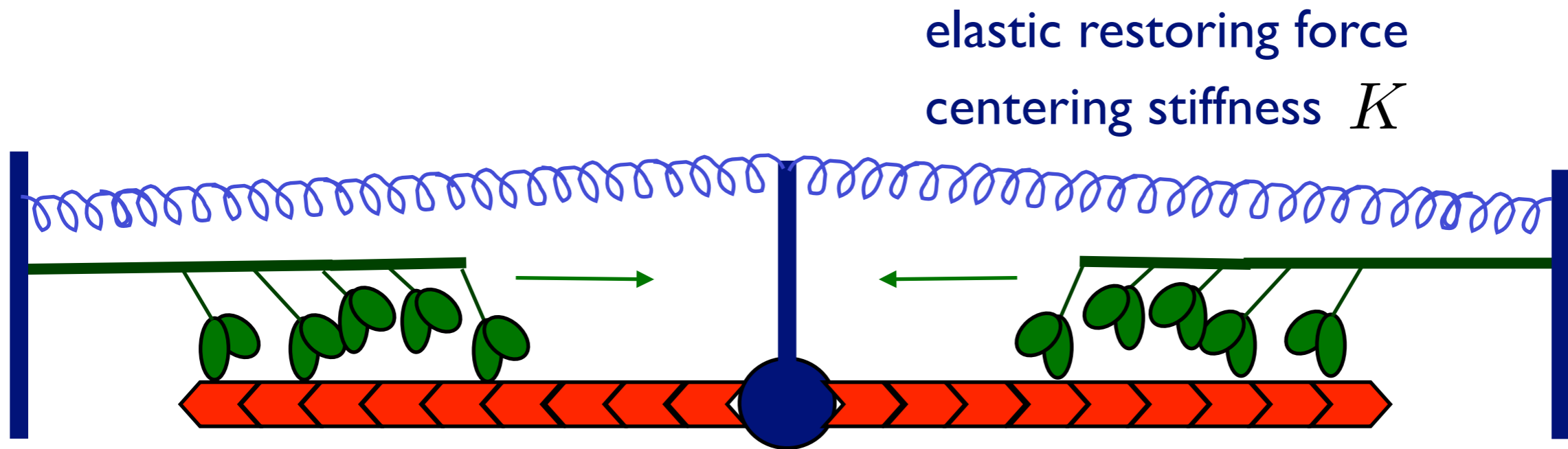
Instability and bistability



bistability

negative friction

Nonlinear oscillator



Effective dynamics

$$m_{\text{eff}} \ddot{x} + (\xi - \Gamma) \dot{x} + Kx + B\dot{x}^3 = 0$$

↑
delays due to
on- and off-rates

↑
negative friction

↑
centering stiffness

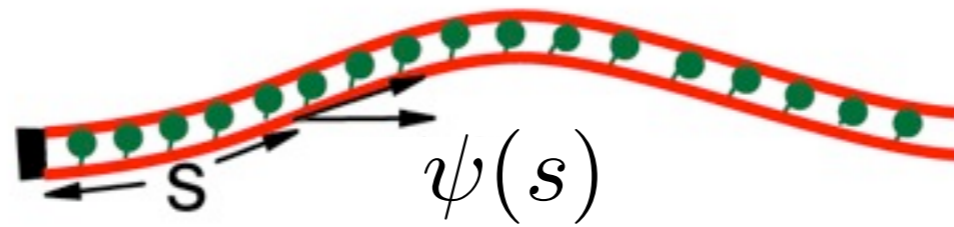
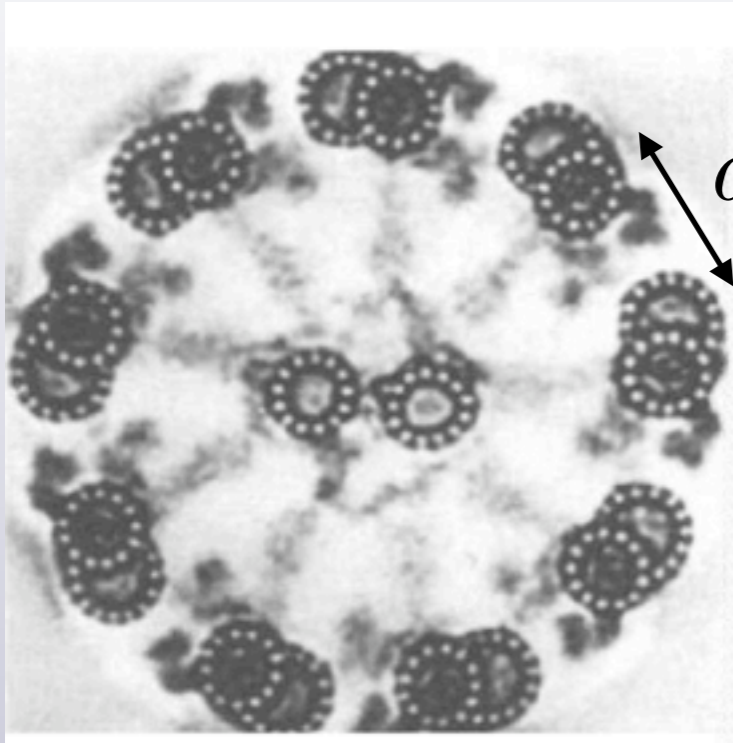
↑
nonlinear effects

Jülicher and Prost, PRL (1997)

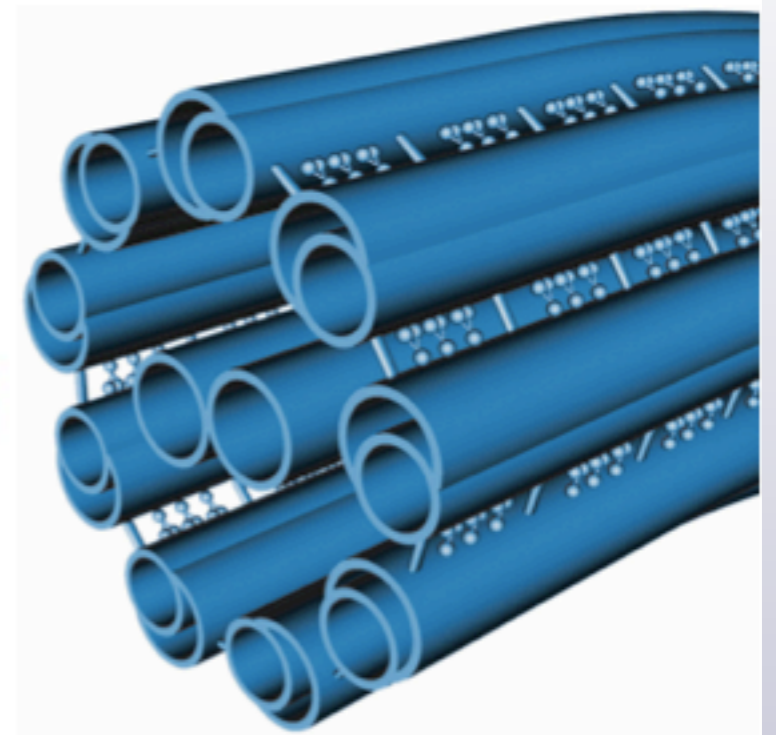
Grill, Kruse, Jülicher PRL (2005)

Pecreaux et. al., Current Biology (2006)

Planar ciliar beat



$$\psi(0) = 0$$



$$G = \int_0^L ds \left(\frac{\kappa}{2} \dot{\psi}^2 + f(s)x(s) \right)$$

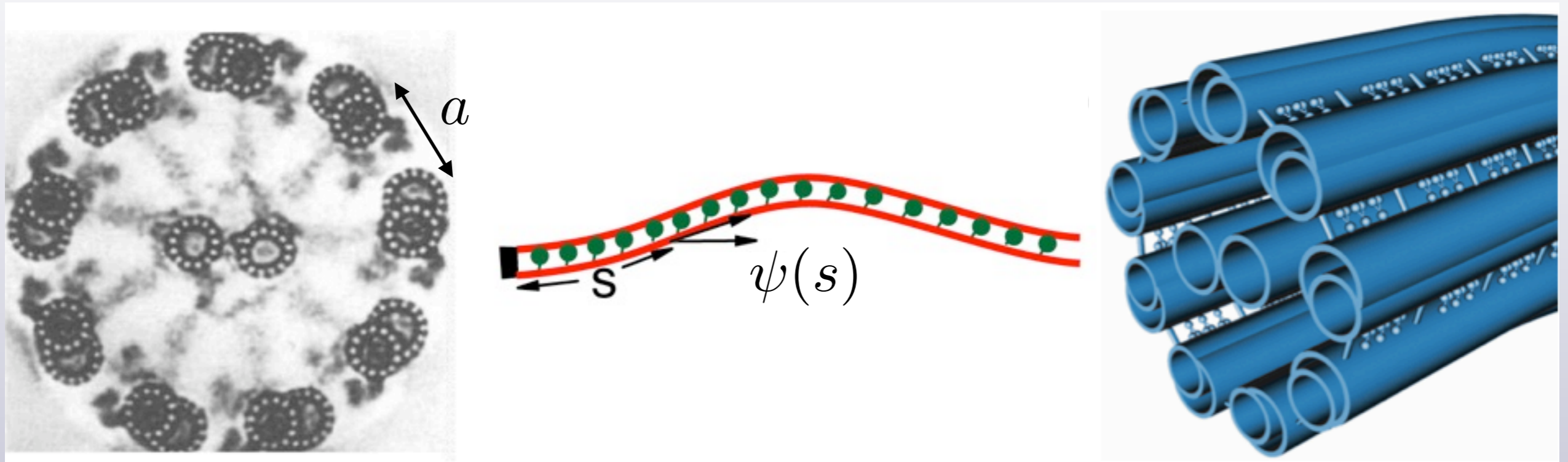
Bending energy + work term

$$x(s) = x_0 + a\psi(s)$$

$x(s)$ motor displacement

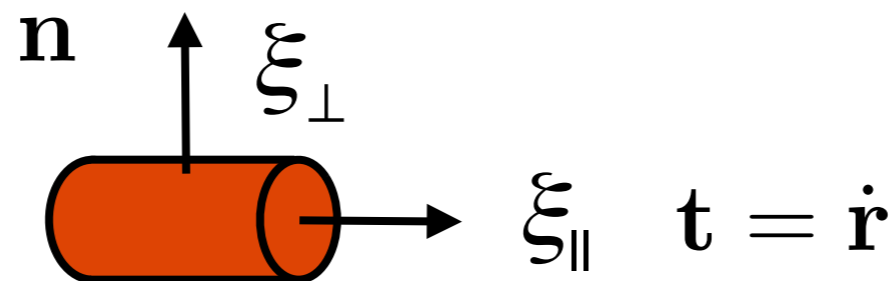
$f(s)$ motor force density

Planar ciliar beat

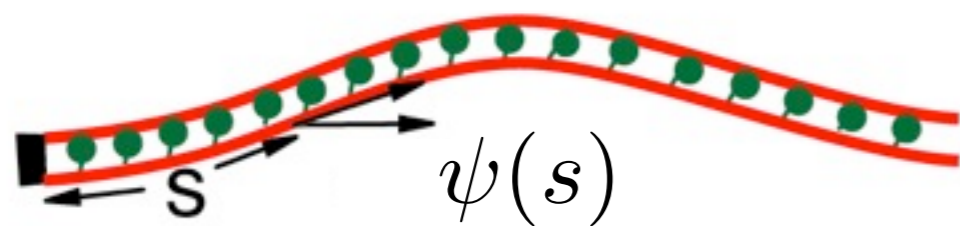


Dynamic equations

$$\partial_t \mathbf{r} = - \left(\frac{1}{\xi_{\perp}} \mathbf{n}\mathbf{n} + \frac{1}{\xi_{\parallel}} \mathbf{t}\mathbf{t} \right) \frac{\delta G}{\delta \mathbf{r}}$$



Linearized dynamics



force density of dynein motors $f(s, t)$
local angle of cilium $\psi(s, t)$

Shape equation for the flagellar beat

$$\xi_{\perp} \partial_t \psi \simeq -\kappa \partial_s^4 \psi + a \partial_s^2 f$$

friction

bending elasticity

motor forces

Sliding control of motors

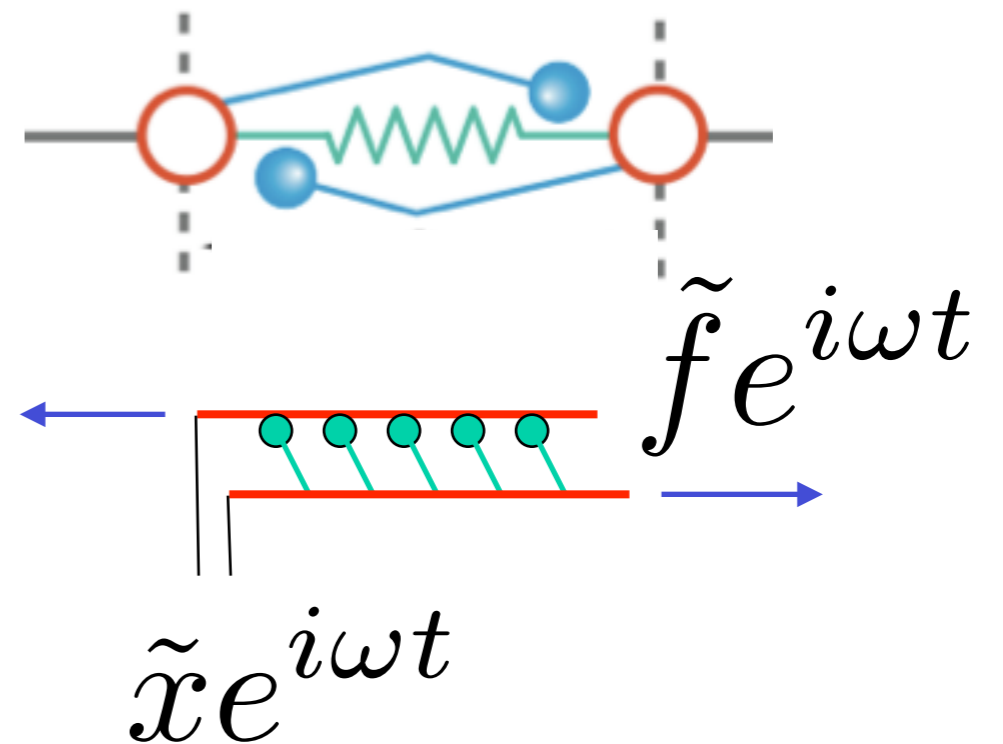
Active material

Linear response

$$\tilde{f} \simeq \chi(\omega) \tilde{x}$$

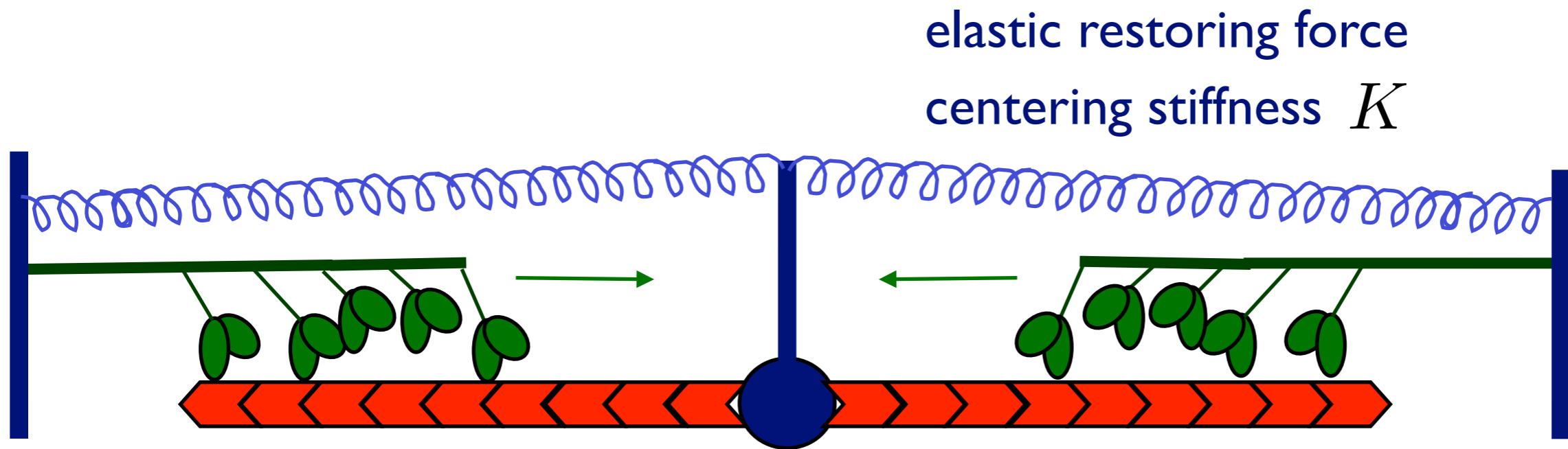
Frequency dependent susceptibility

$$\chi = k + i\lambda\omega$$



$$x(s) = x_0 + a\psi(s)$$

Nonlinear oscillator



Effective dynamics

$$m_{\text{eff}} \ddot{x} + (\xi - \Gamma) \dot{x} + Kx + B\dot{x}^3 = 0$$

↑
delays due to
on- and off-rates

↑
negative friction

↑
centering stiffness

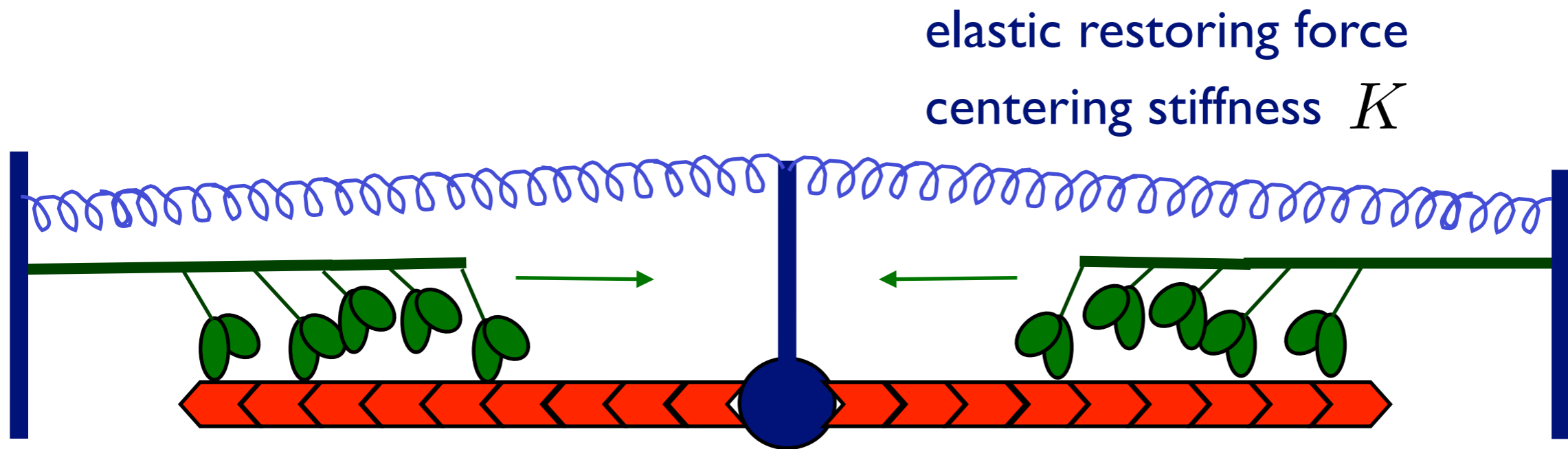
↑
nonlinear effects

Jülicher and Prost, PRL (1997)

Pecreaux et. al., Current Biology (2006)

Riedel, Hilfinger, Howard, Jülicher, HFSP J. (2007)

Motor response function



linear motor response

$$\chi(\omega) = -m_{\text{eff}}\omega^2 + i(\xi - \Gamma)\omega + K$$

↑
delays due to
on- and off-rates

↑
negative friction

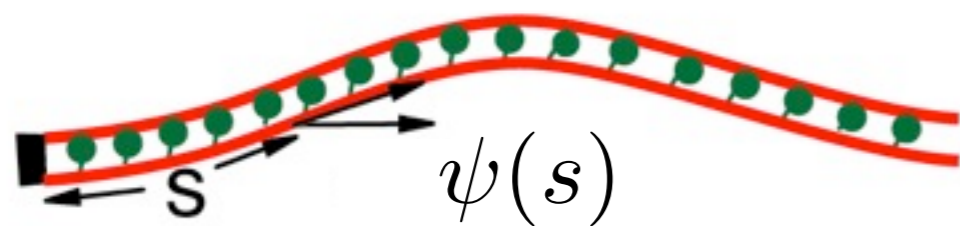
↑
centering stiffness

Jülicher and Prost, PRL (1997)

Pecreaux et. al., Current Biology (2006)

Riedel, Hilfinger, Howard, Jülicher, HFSP J. (2007)

Linear wave equation



sliding control

$$\tilde{f} \simeq \chi(\omega)\tilde{x}$$

local angle of cilium

$$\psi(s, t)$$

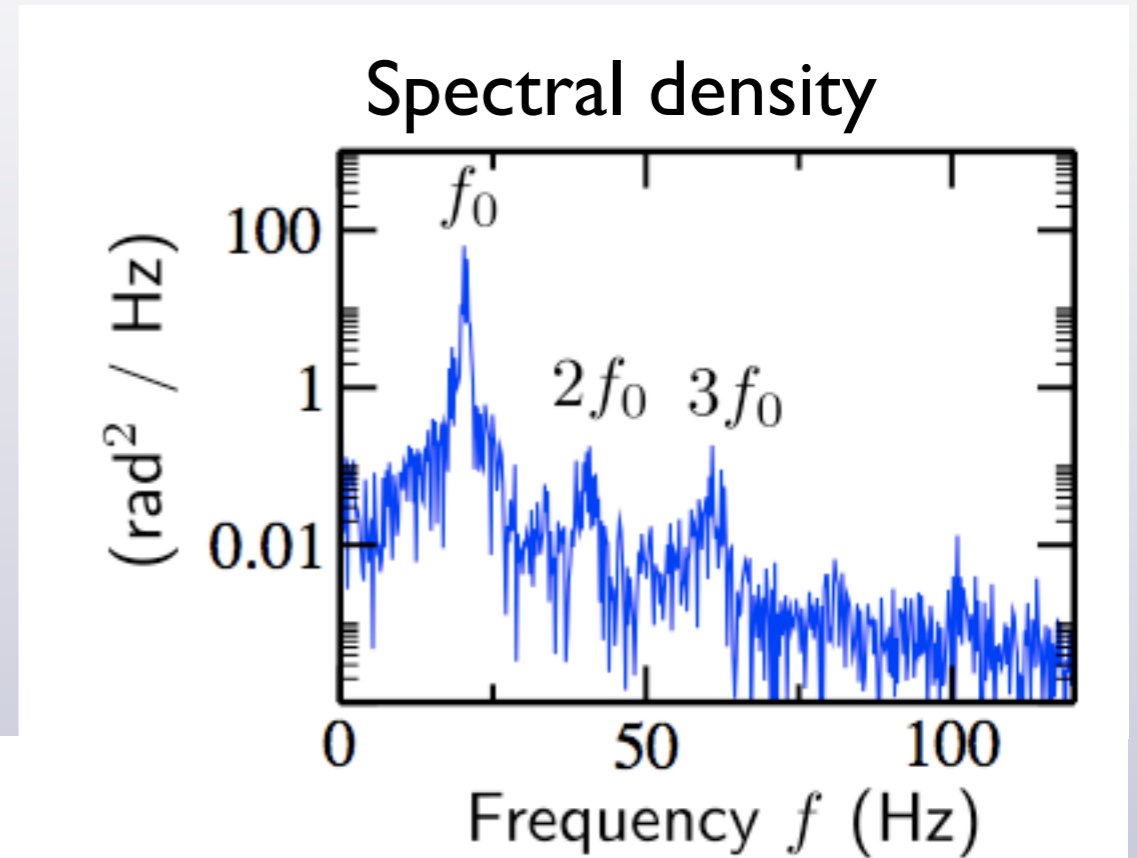
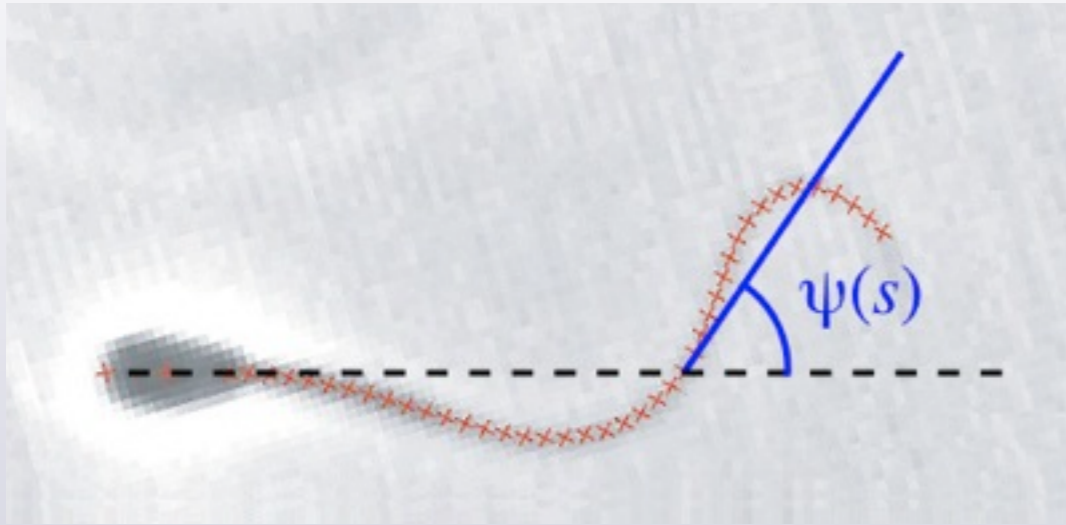
$$i\omega\xi_{\perp}\tilde{\psi} \simeq -\kappa\partial_s^4\tilde{\psi} + a^2\chi\partial_s^2\tilde{\psi}$$

friction

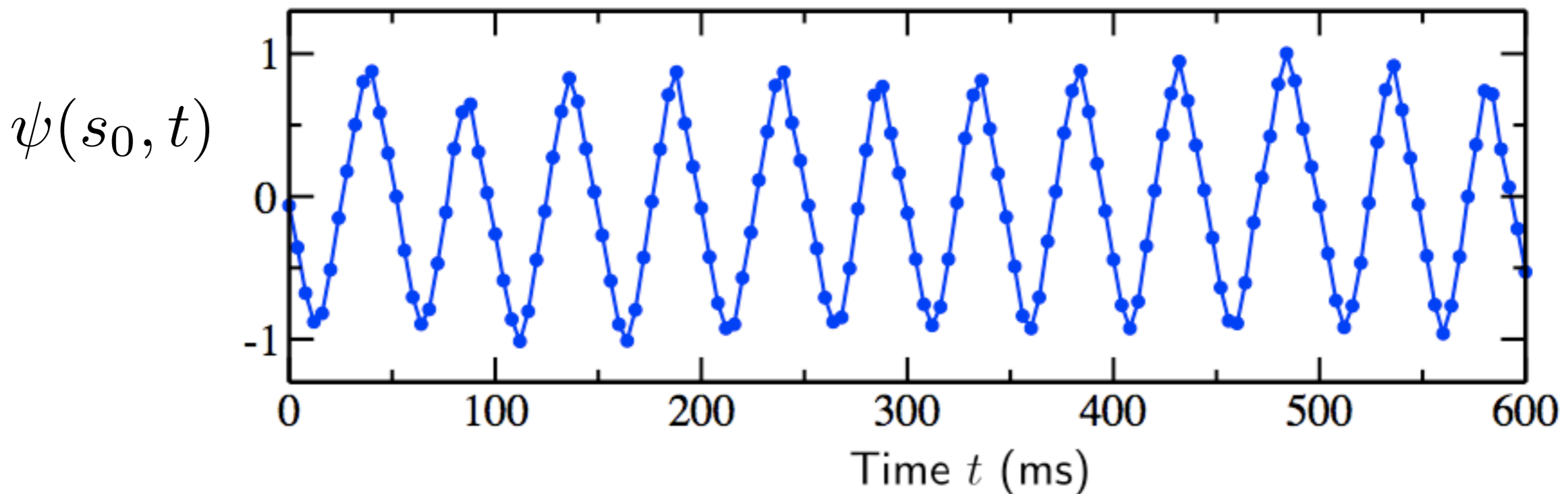
bending elasticity

motor forces

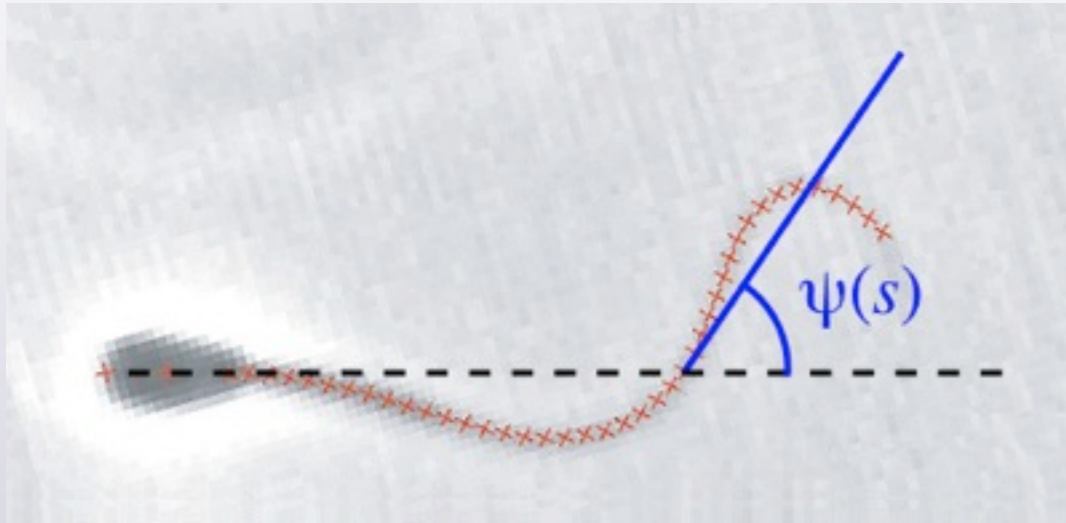
Experimental results



Angle as a function of time at fixed place



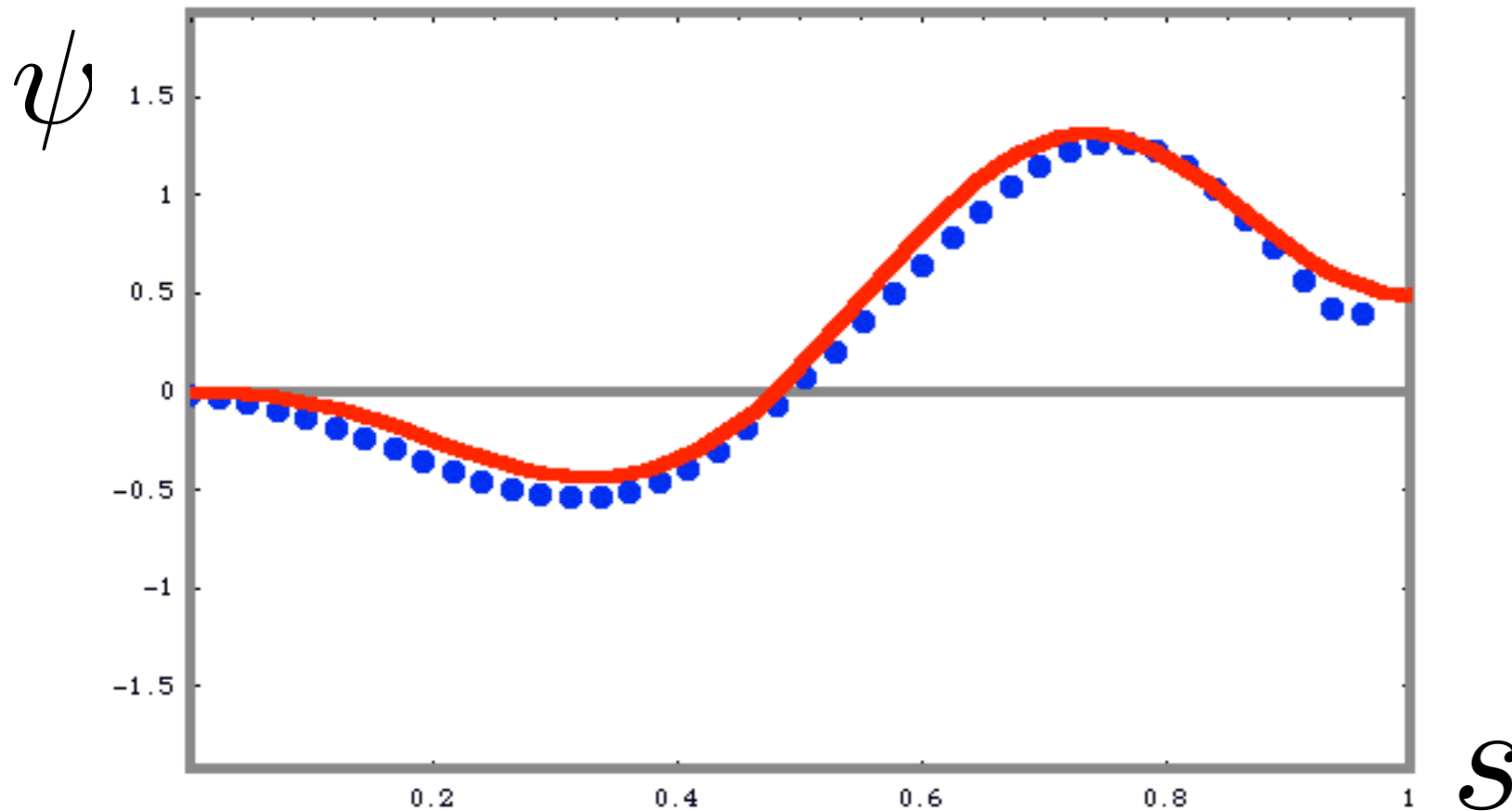
Theory-Experiment



Sliding control



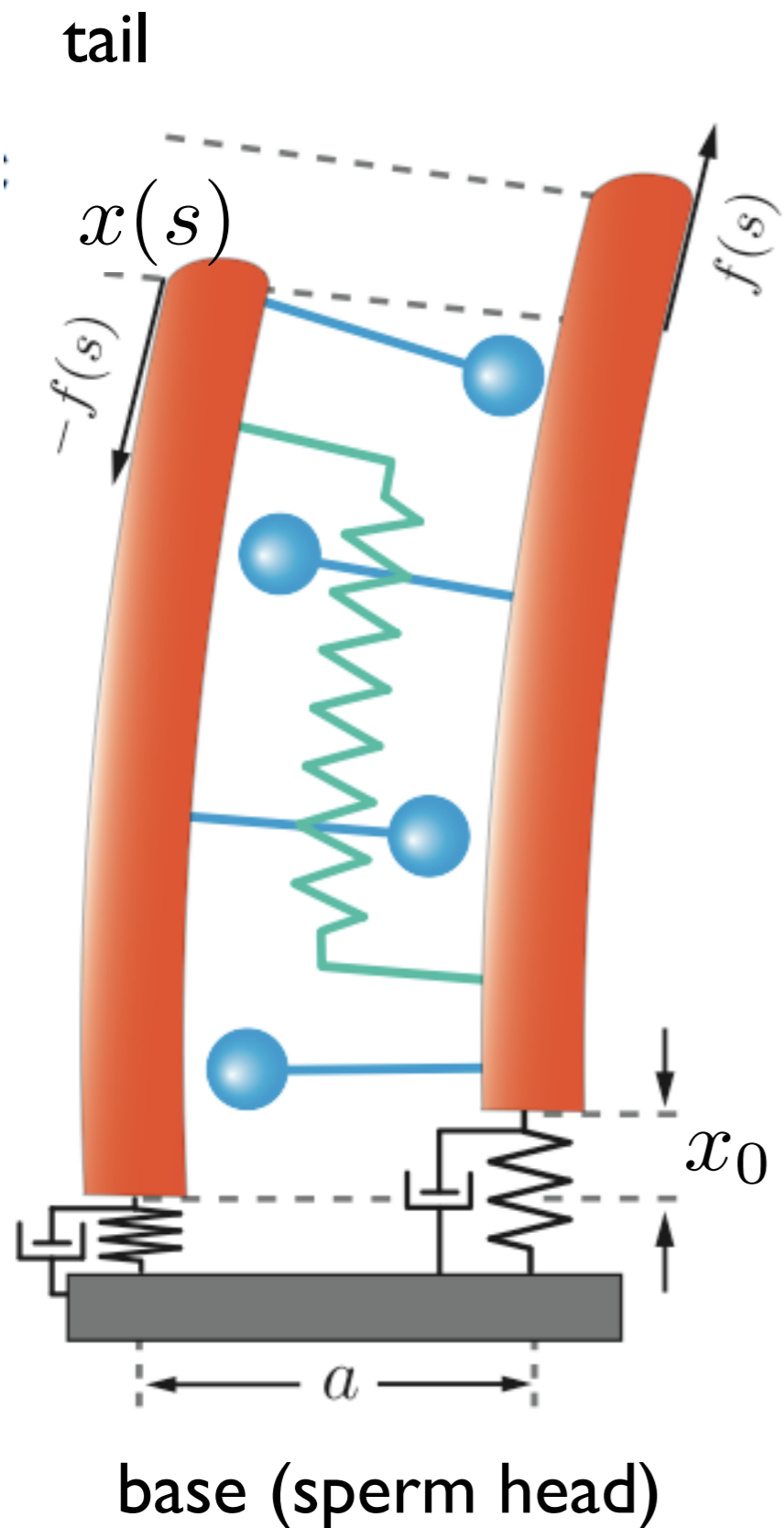
$$\psi(s, t) = \tilde{\psi}(s)e^{i\omega t}$$



theory

experiment

Basal sliding



Basal sliding

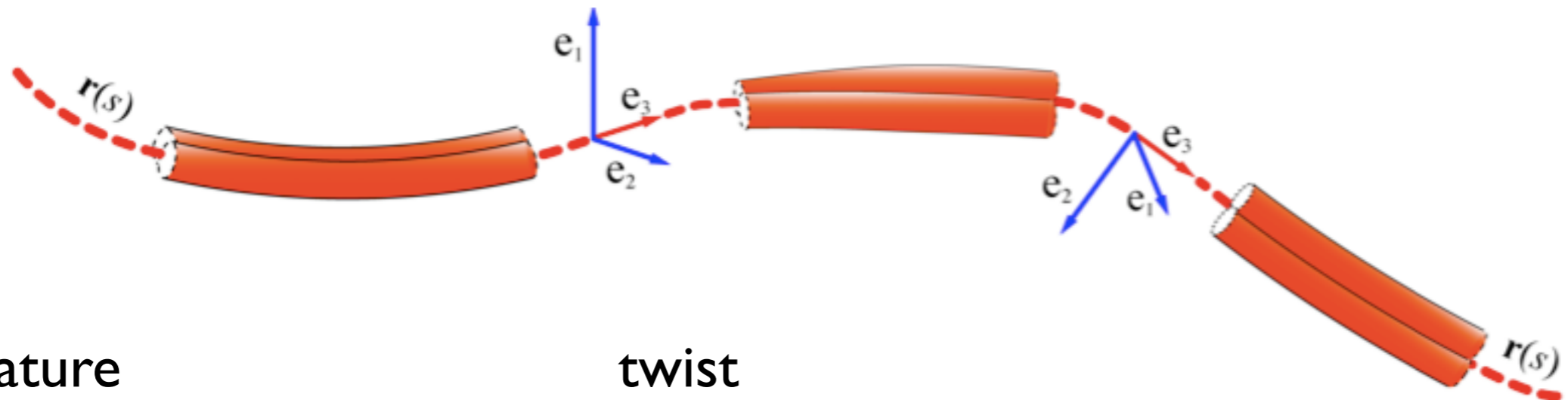
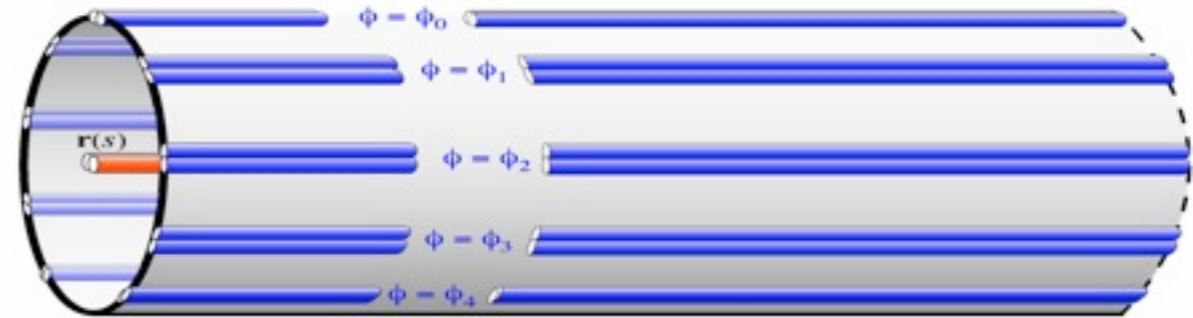
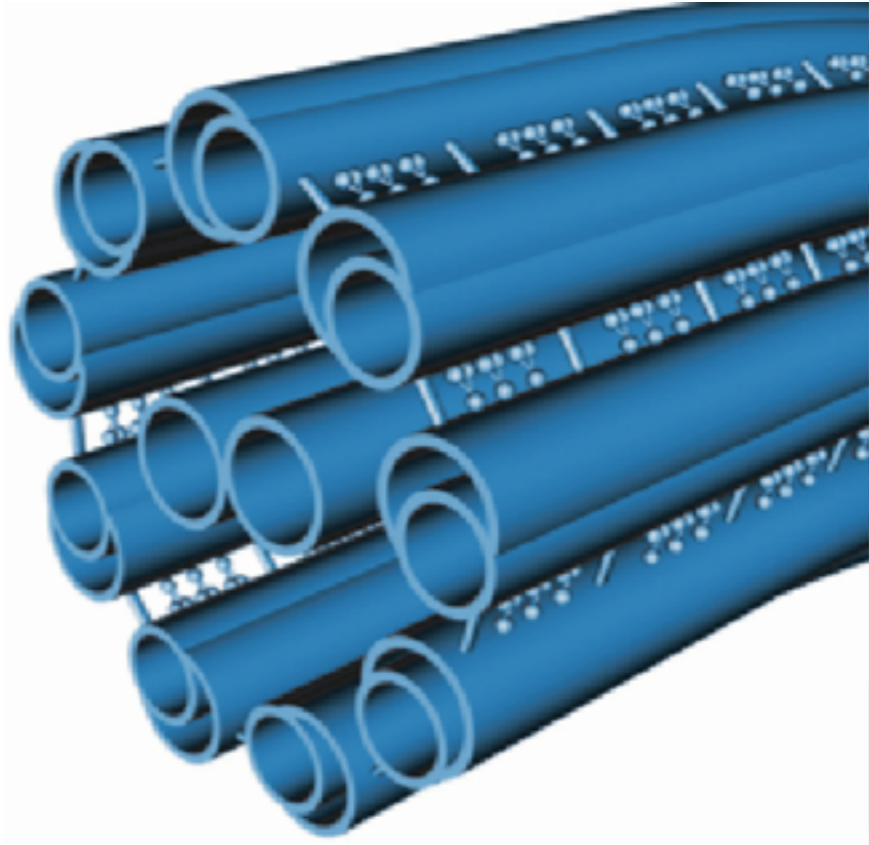
$$x(s) = x_0 + a\psi(s)$$

basal sliding $x_0(t)$

$$|\tilde{x}_0| \simeq 160\text{nm}$$

basal compliance

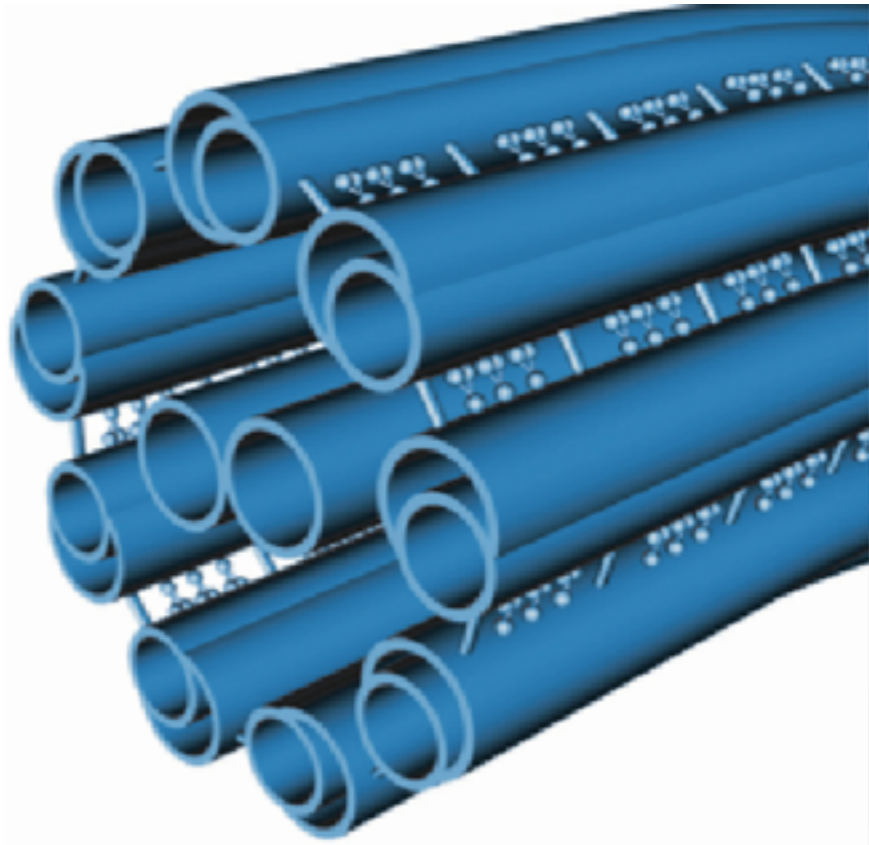
Ciliary beat in three dimensions



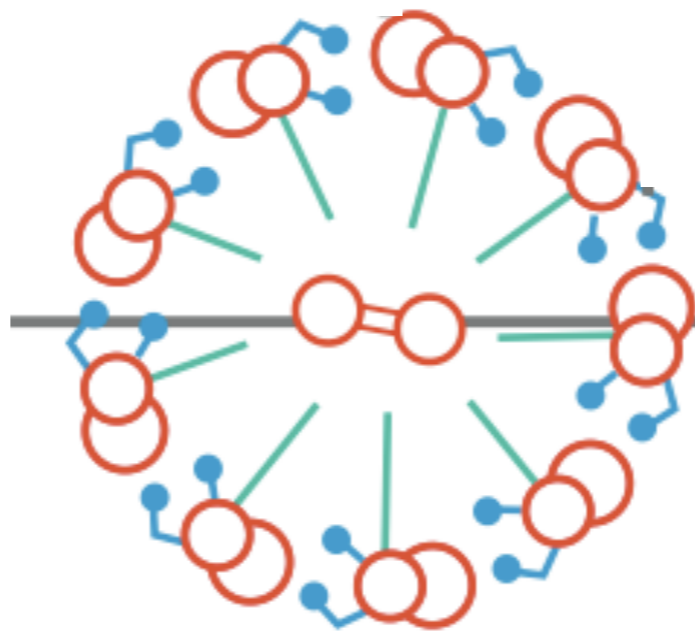
curvature

twist

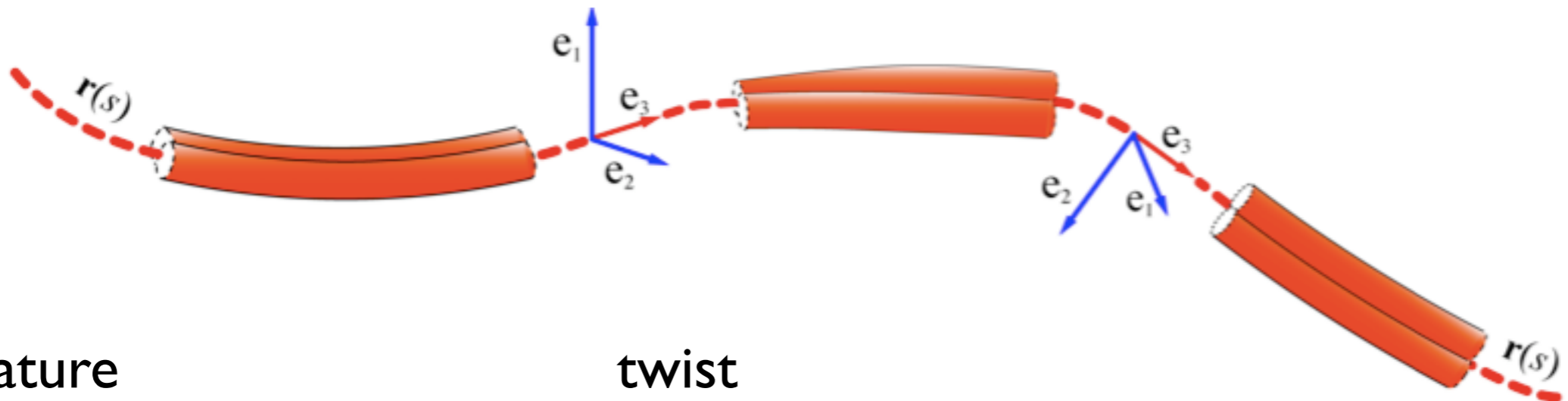
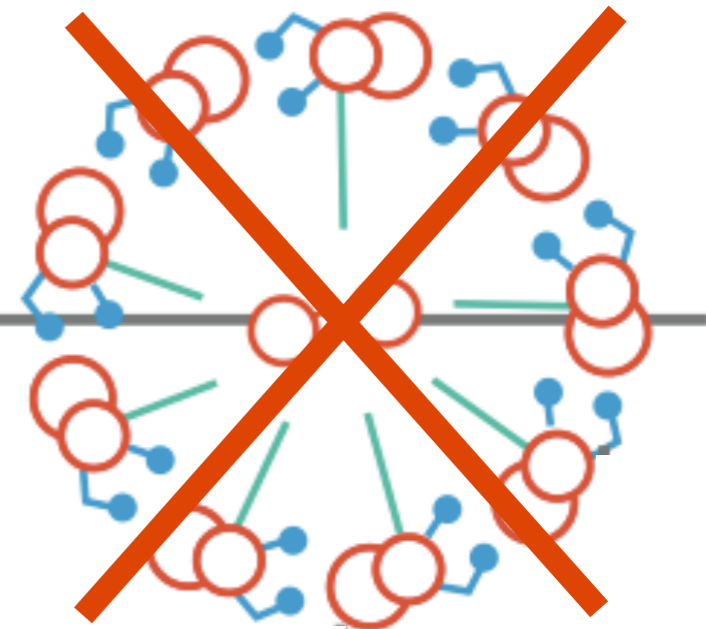
Chirality



left handed



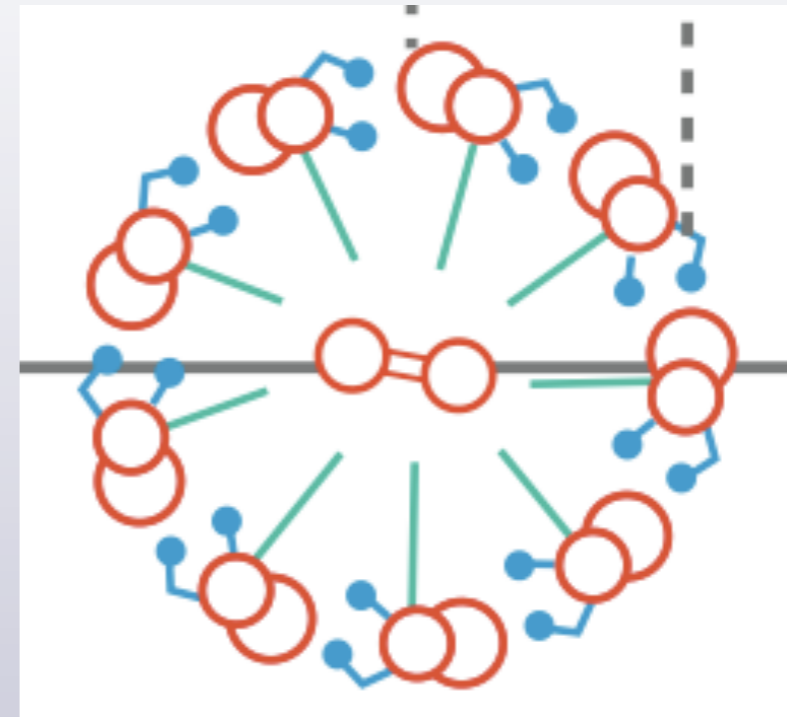
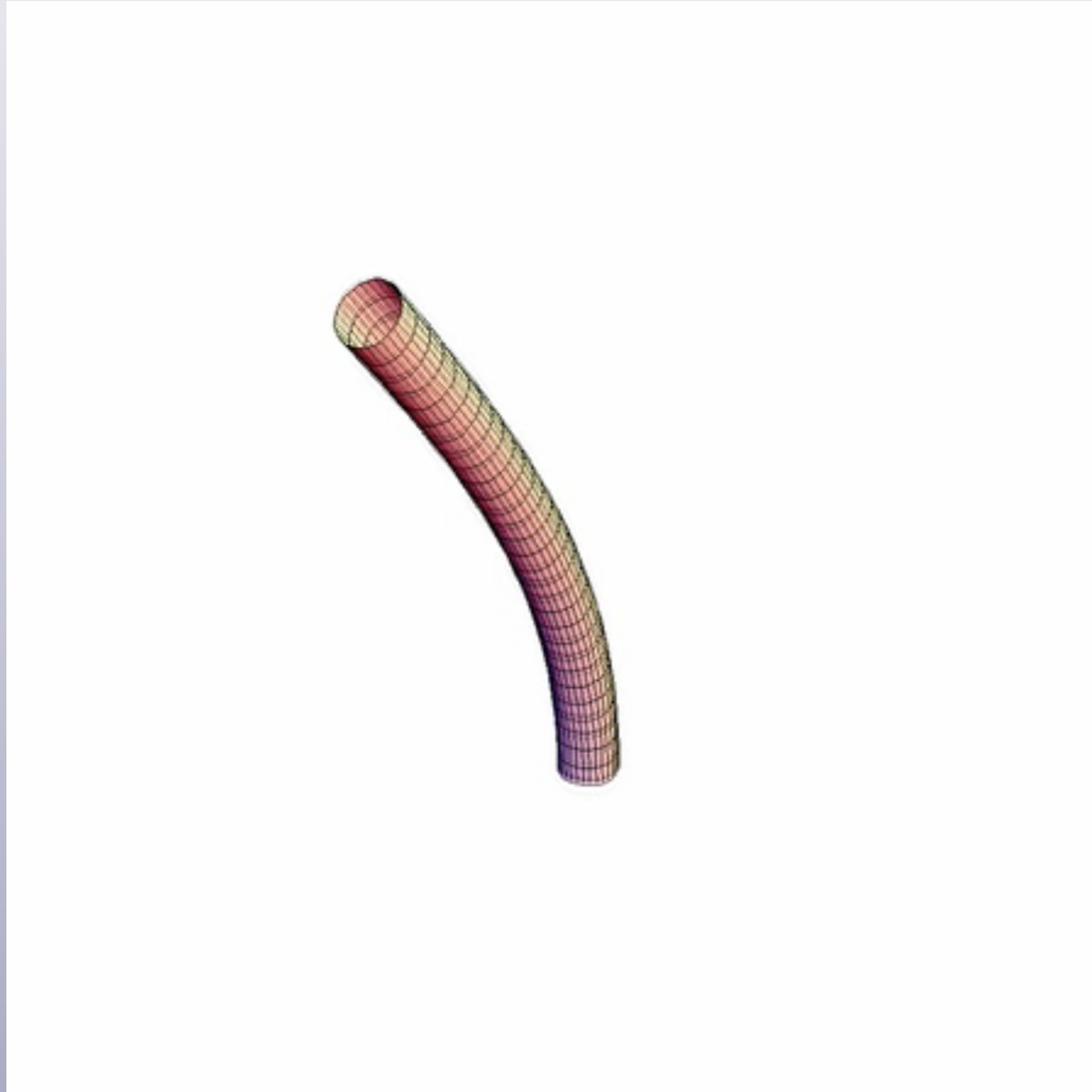
right handed



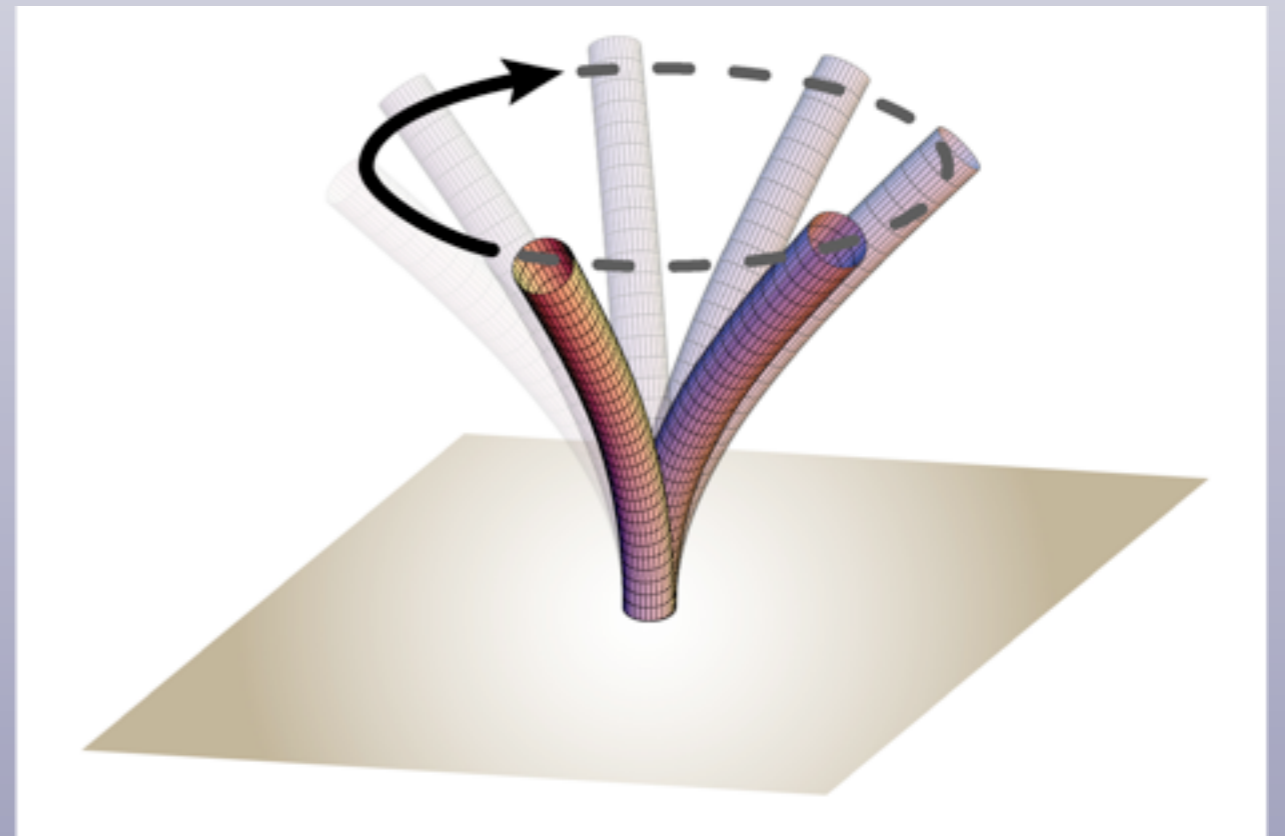
curvature

twist

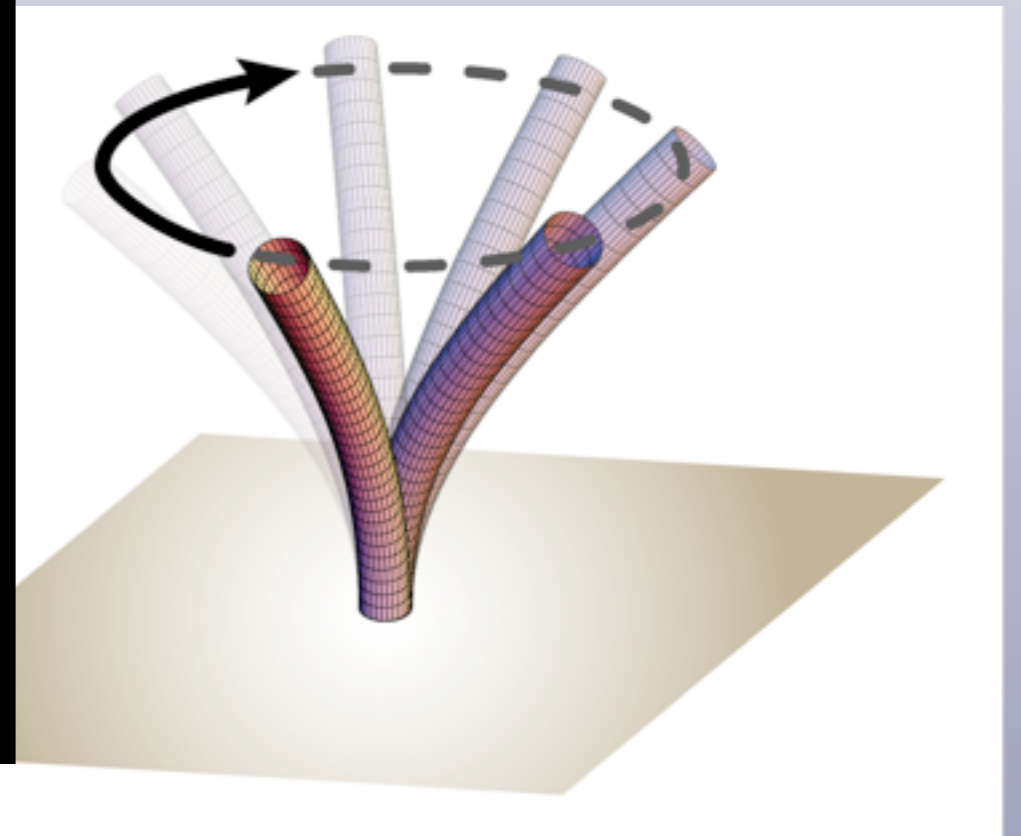
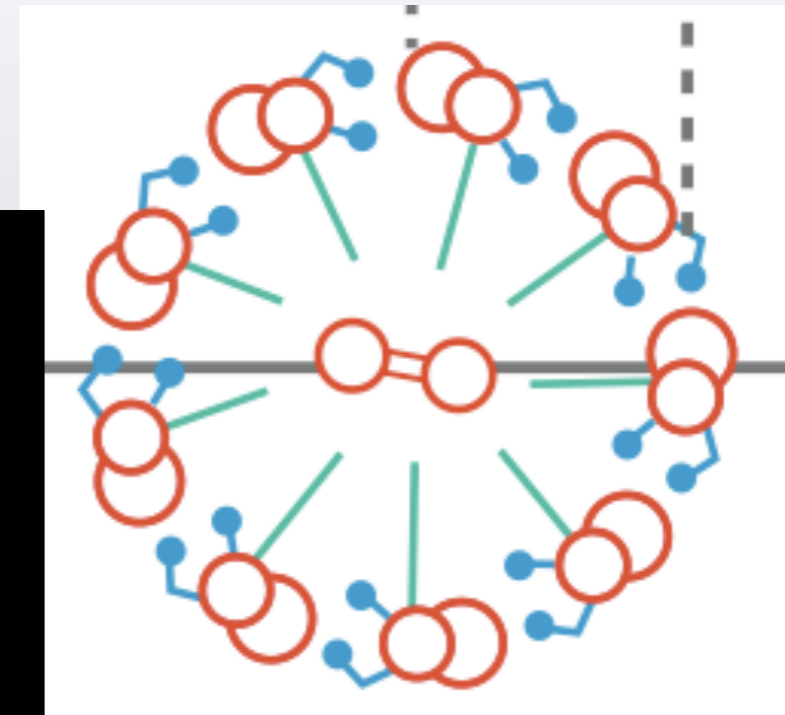
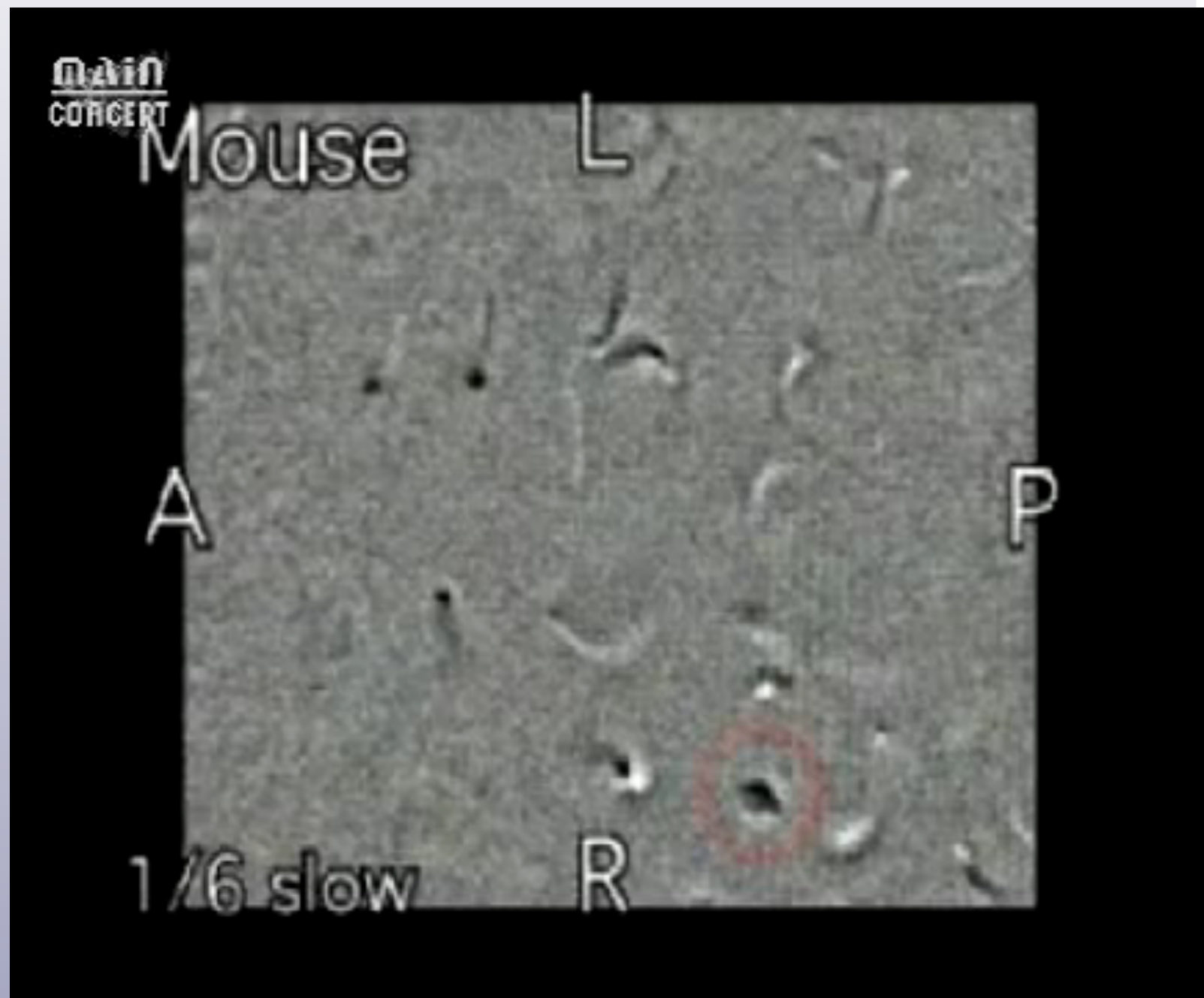
Rotating waves



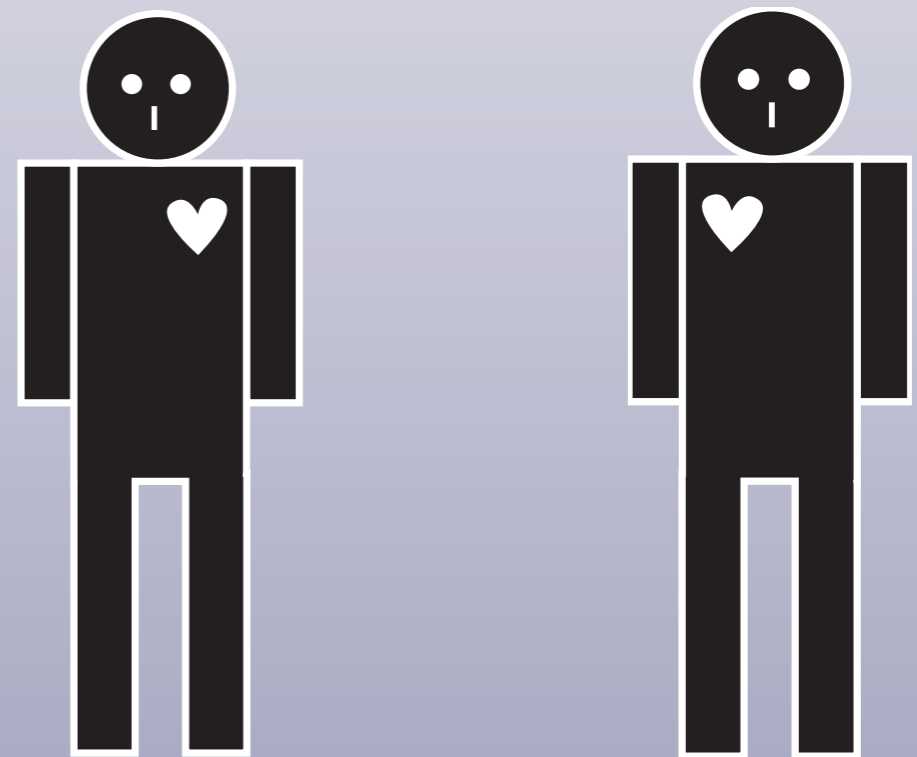
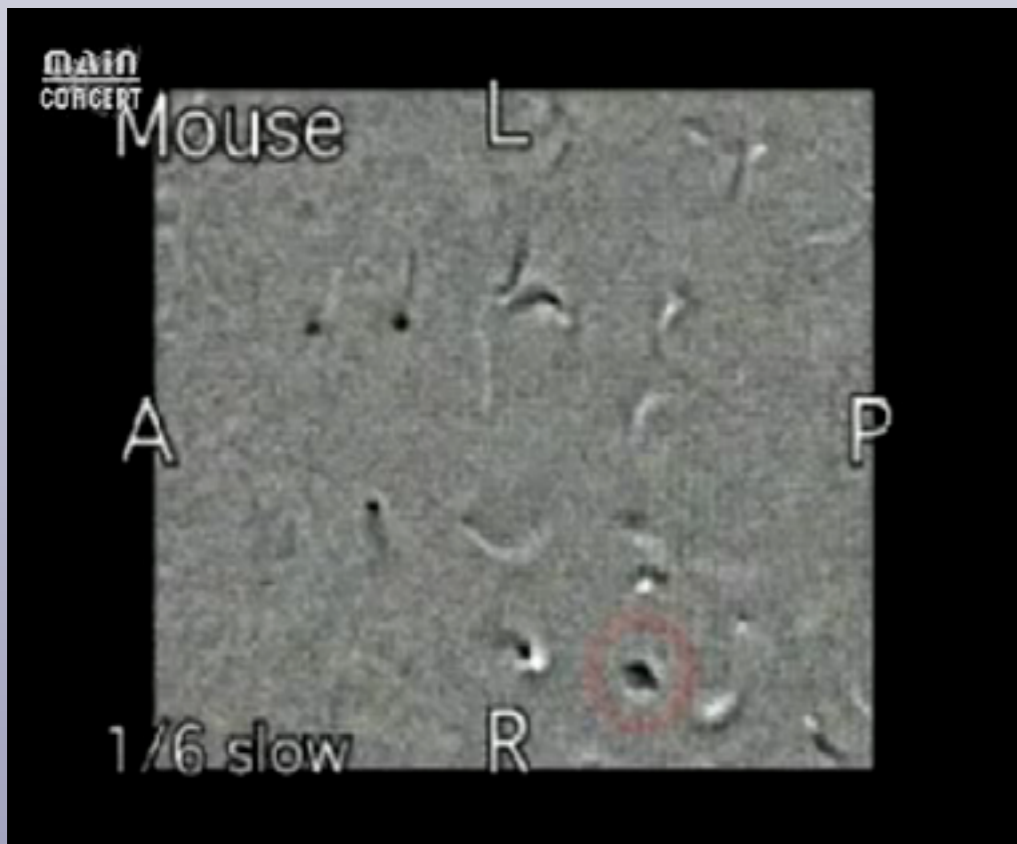
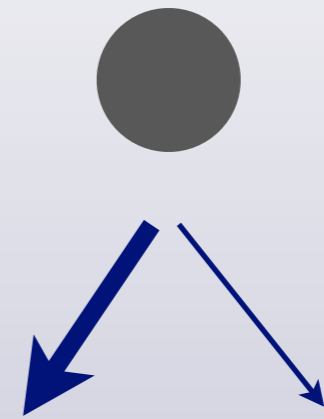
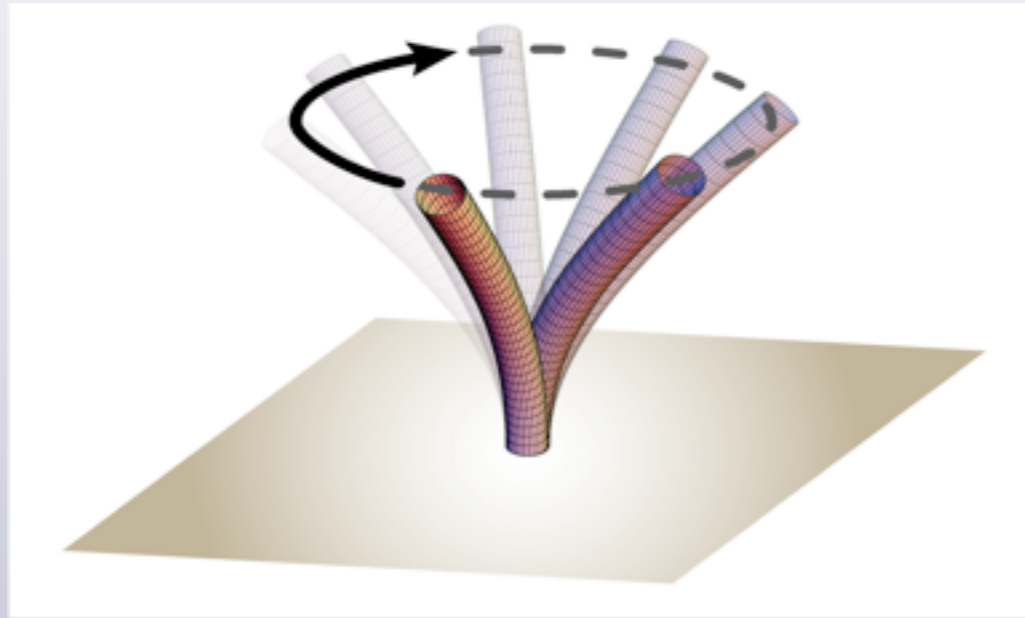
chiral
cilium



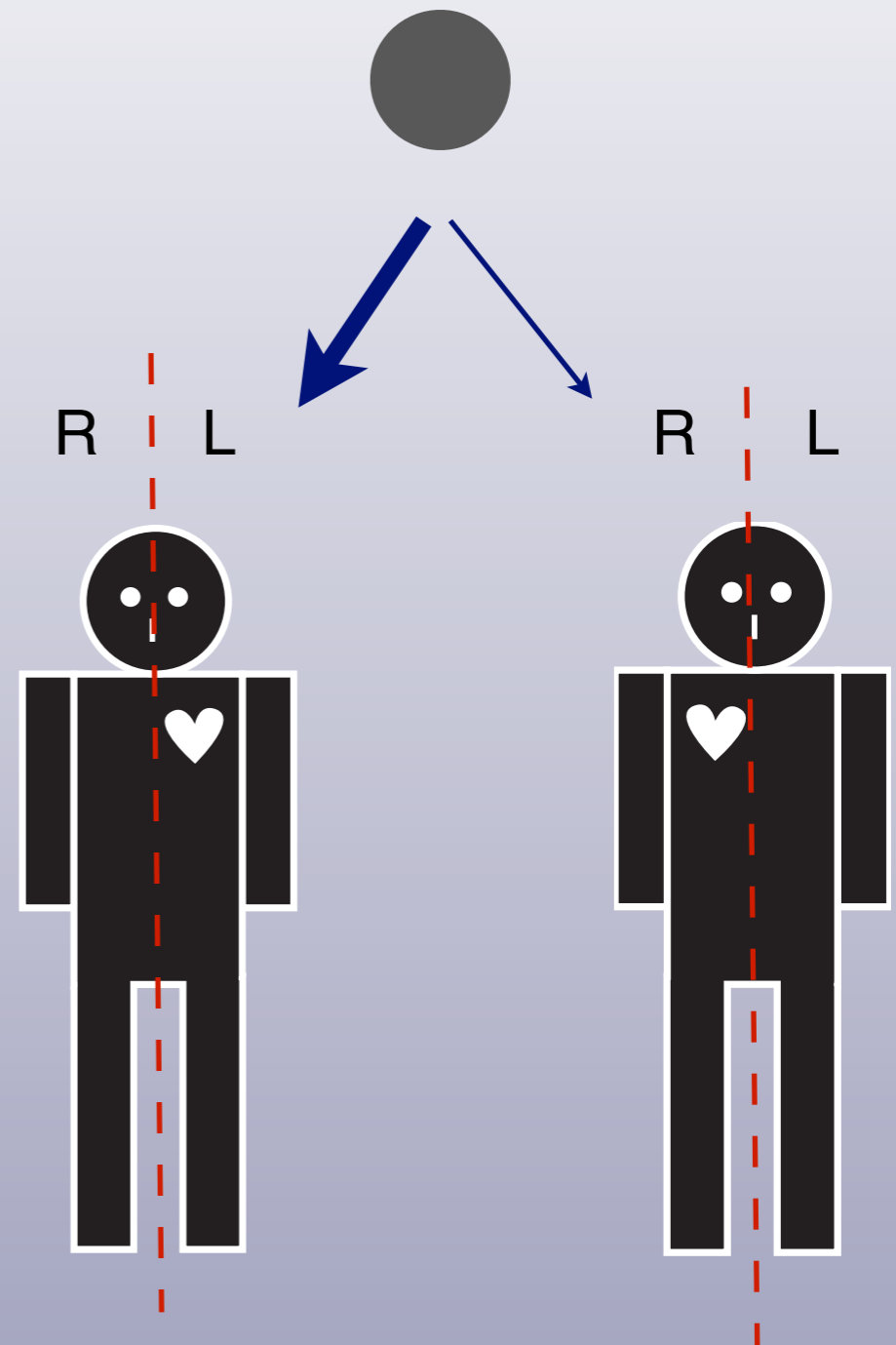
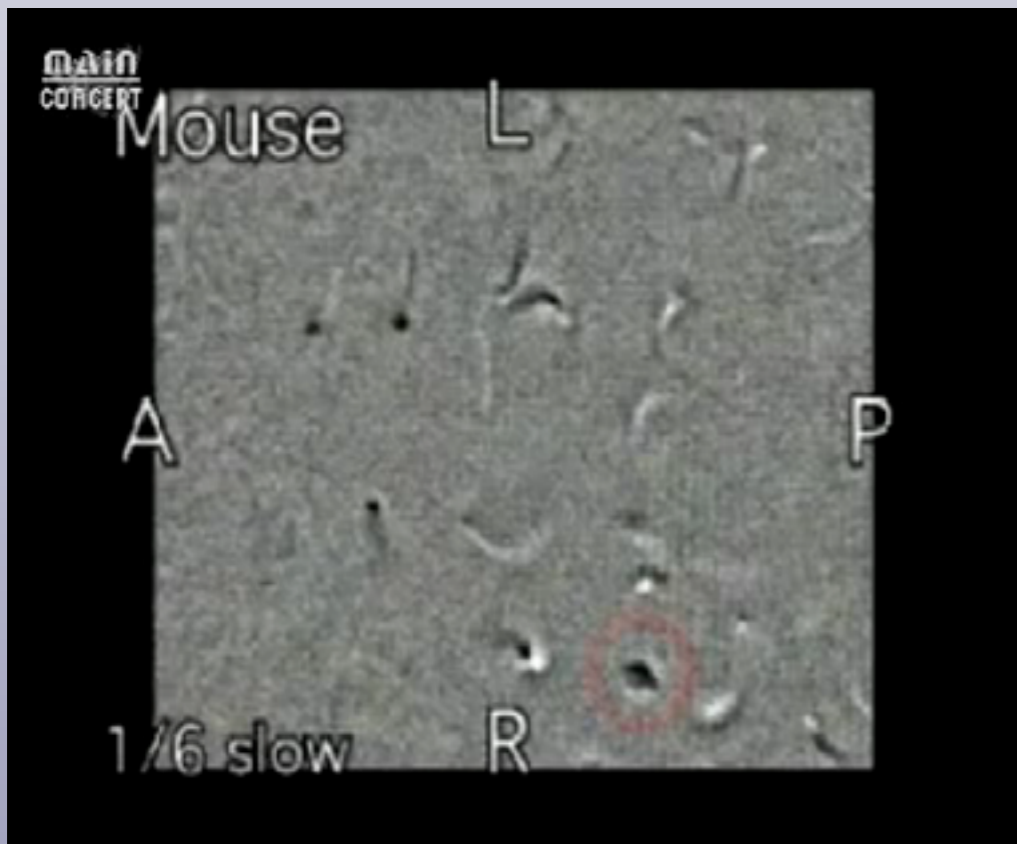
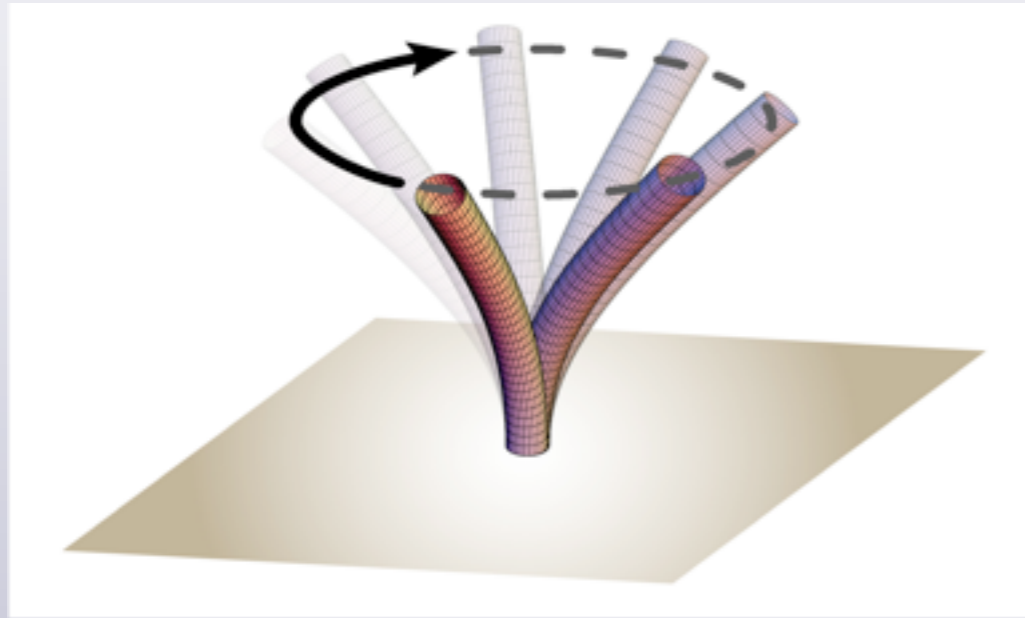
Rotating waves



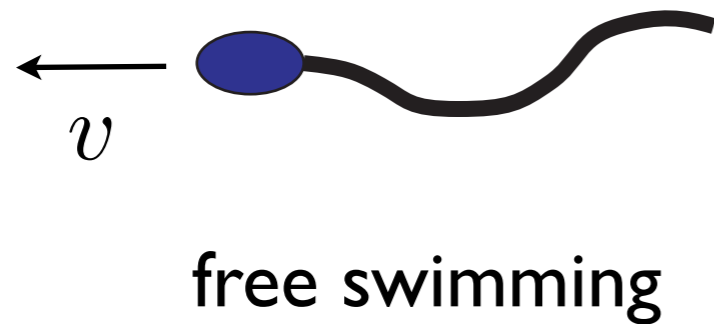
left-right asymmetry



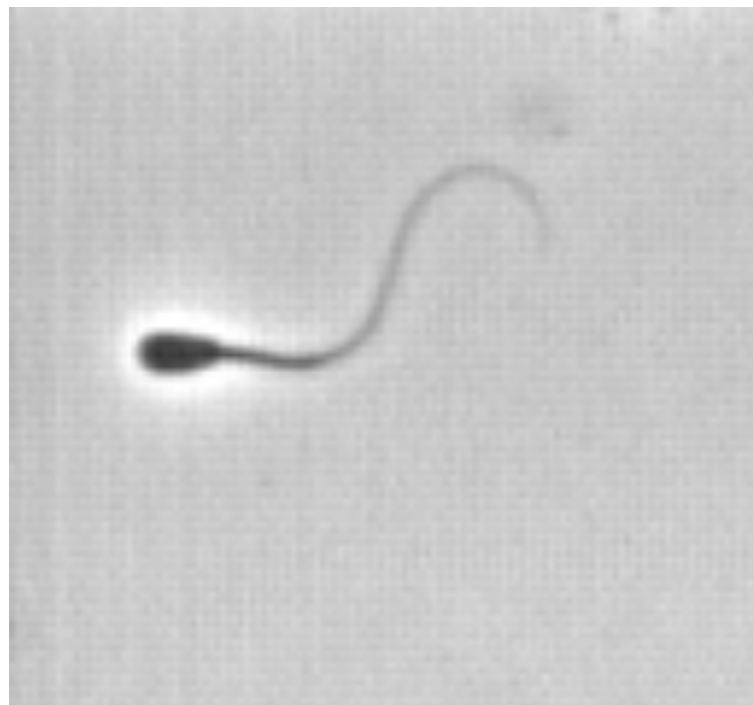
left-right asymmetry



Flagellar beat and swimming



free swimming



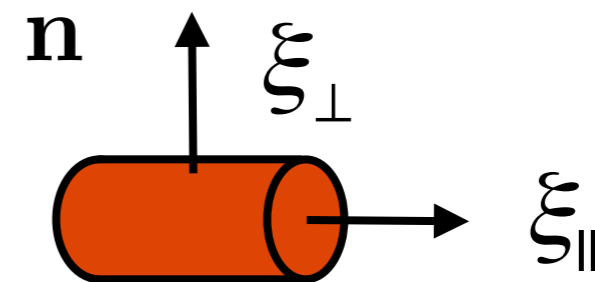
Bull sperm
20 Hz slow motion

no net force

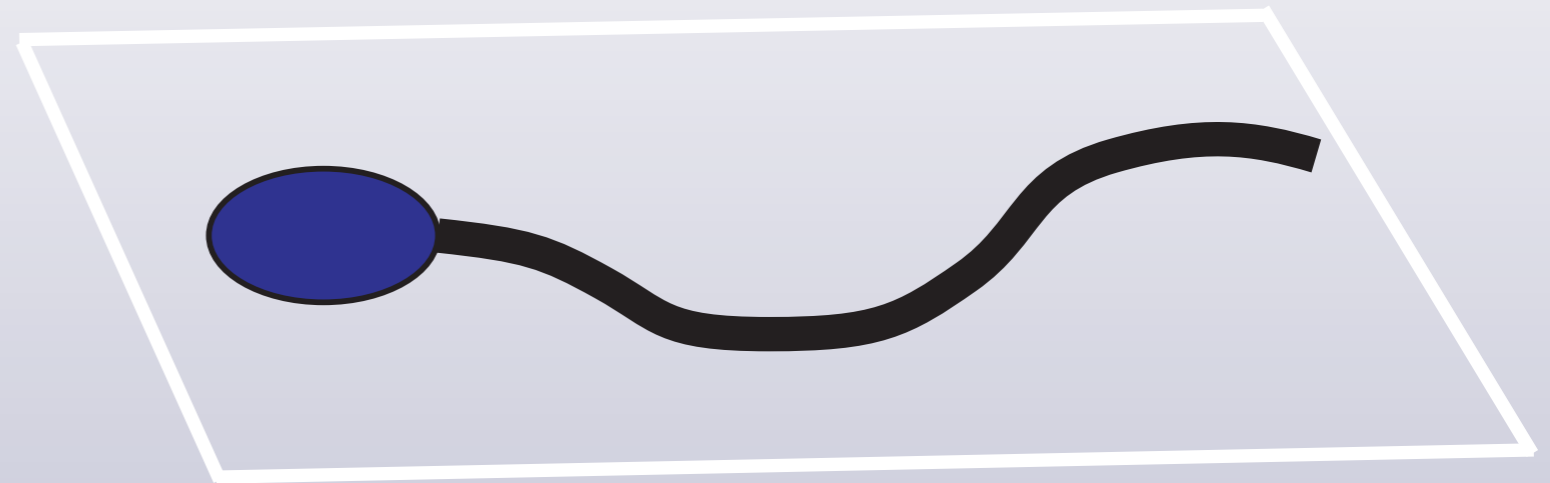
no net torque

translation velocity \mathbf{V}

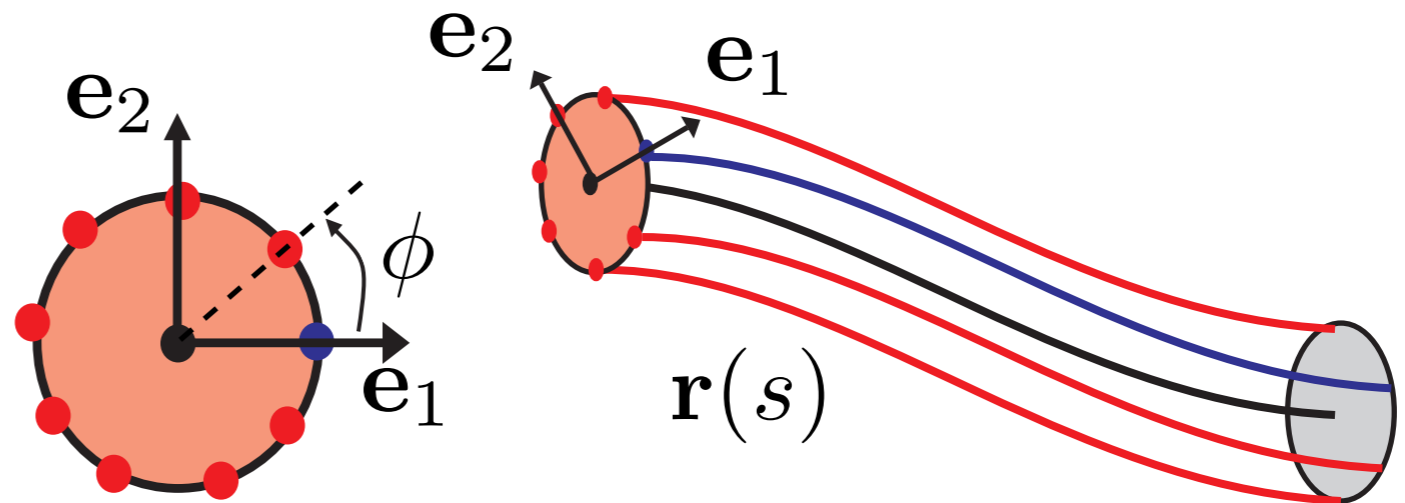
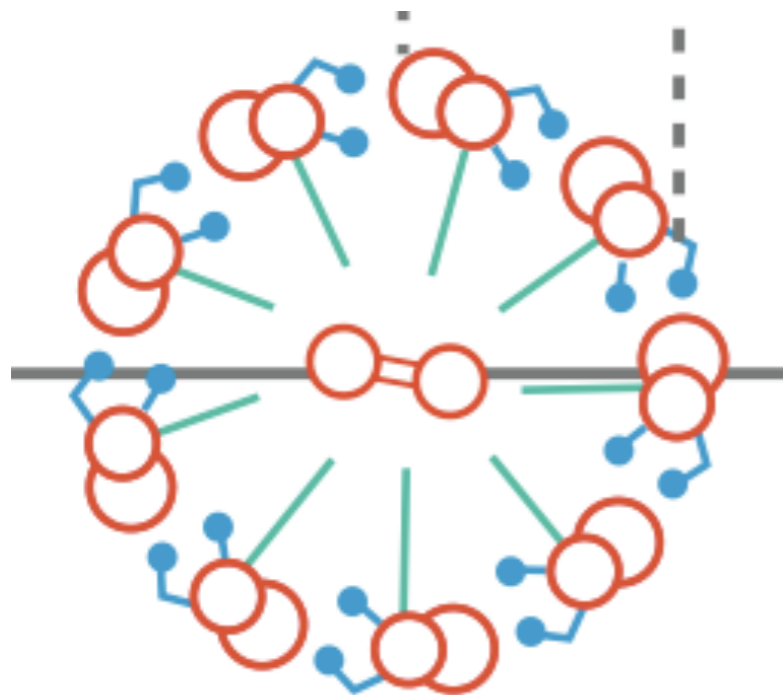
rotation rate Ω



Chiral swimmers



Plane of flagellar beat



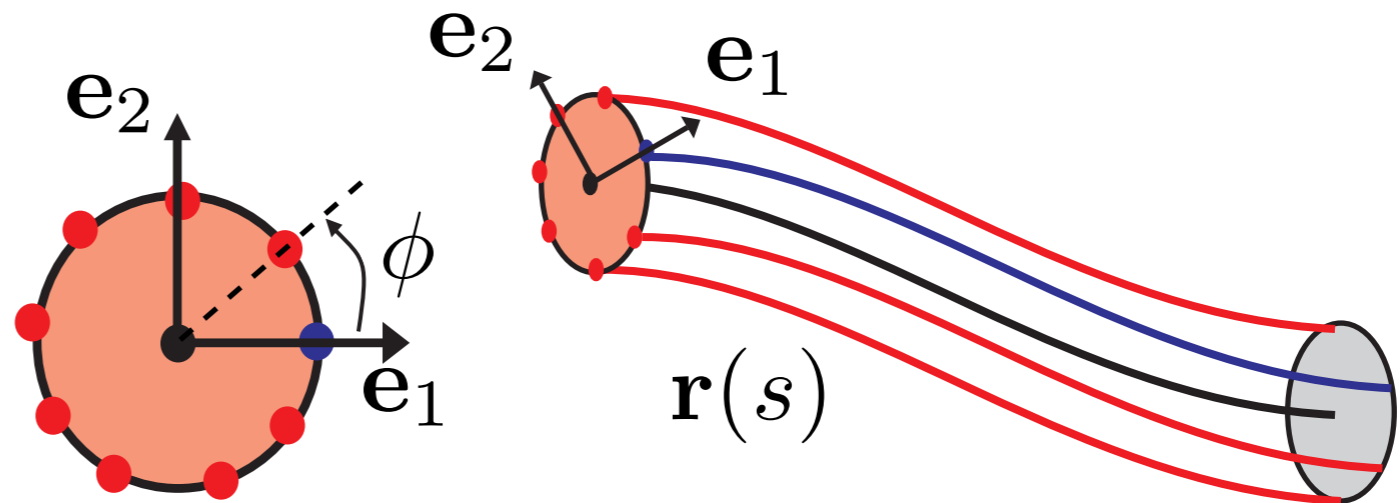
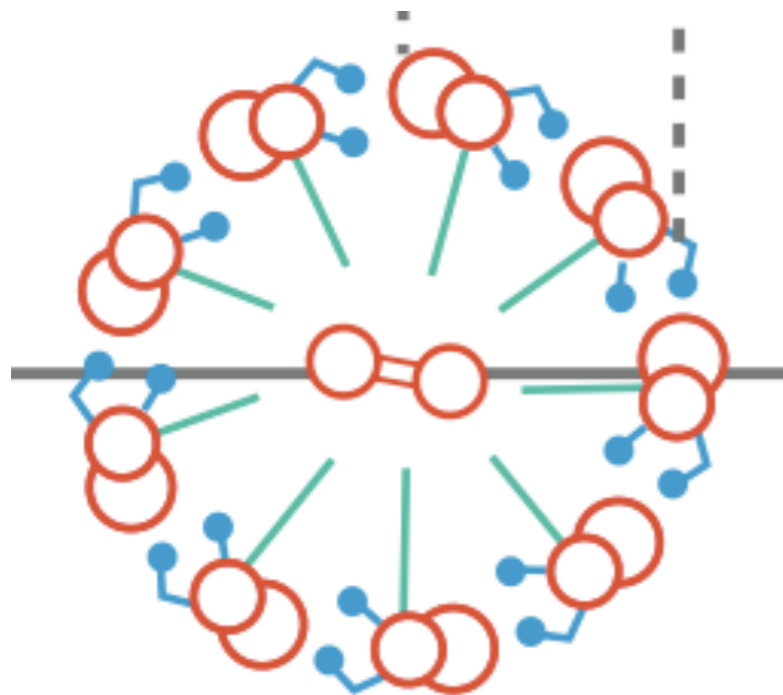
Chiral swimmers



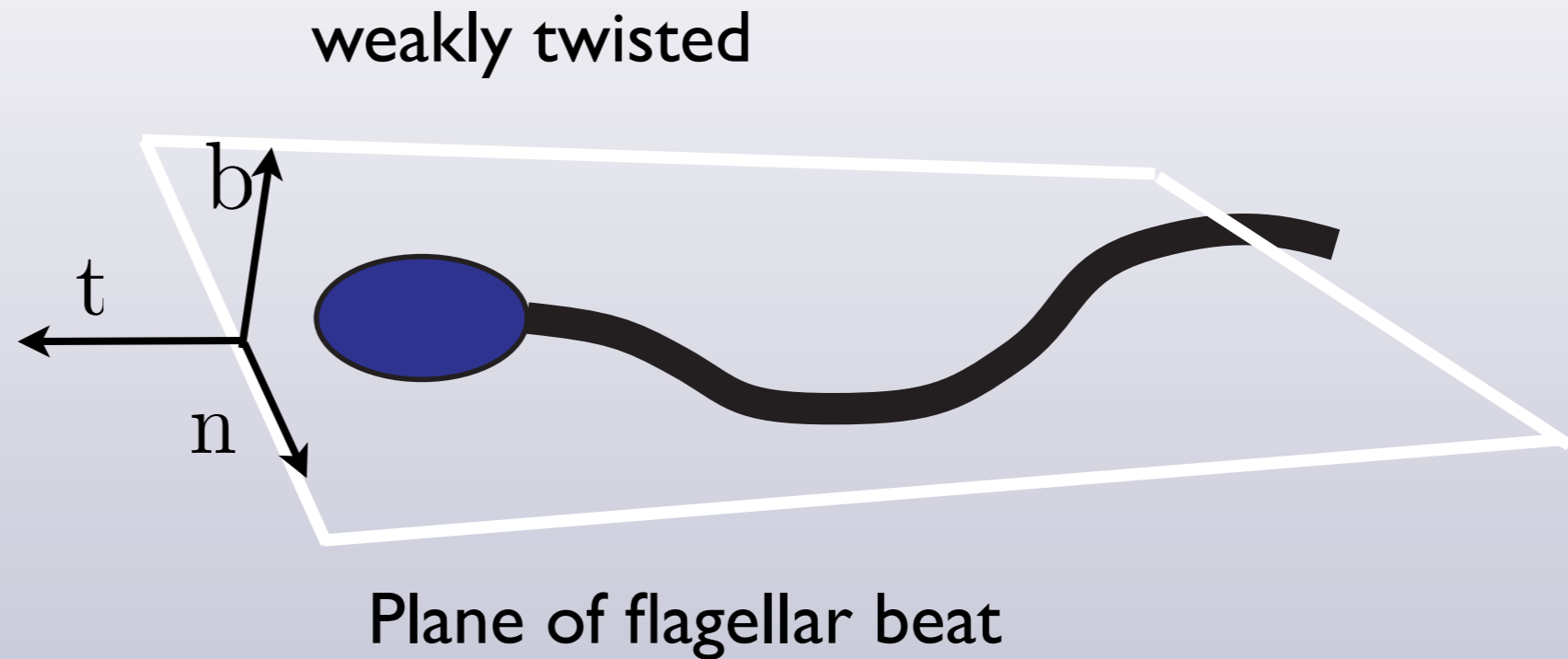
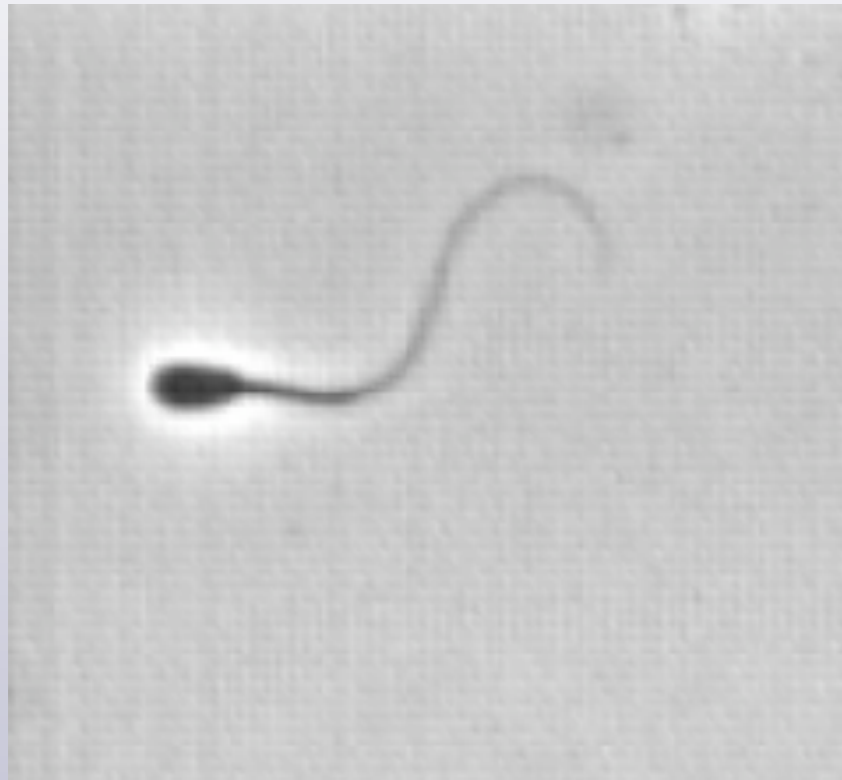
weakly twisted



Plane of flagellar beat



Chiral swimmers



Translation $\mathbf{v} = v_0 \mathbf{t}$

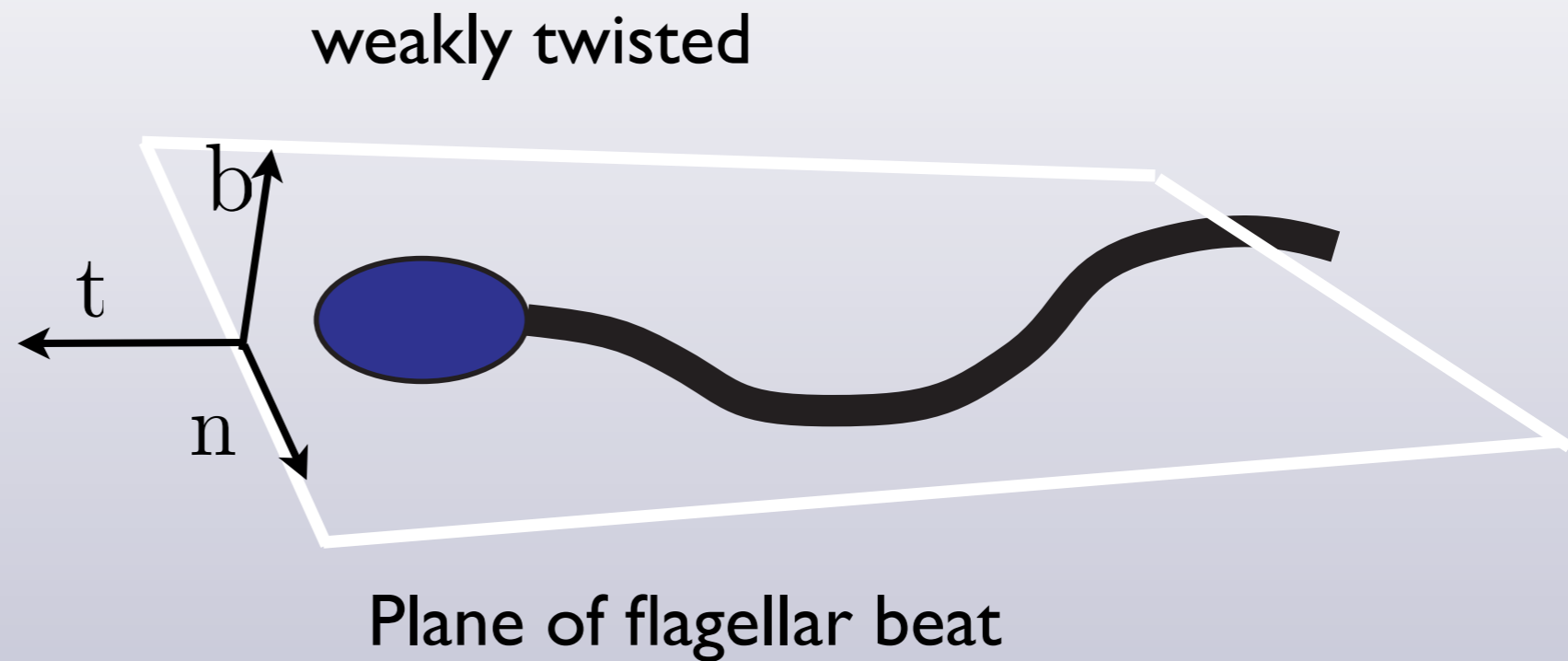
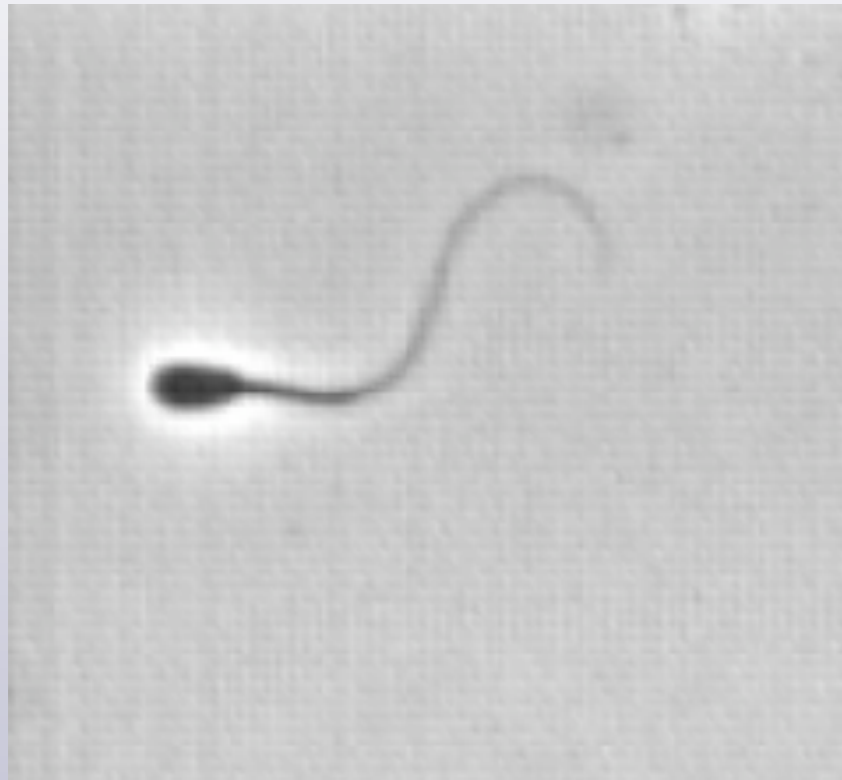
generated by flagellar beat

Rotation $\boldsymbol{\Omega} = \omega_{\parallel} \mathbf{t} + \omega_{\perp} \mathbf{b}$

Curvature $\kappa = \omega_{\perp} / v_0$

Torsion $\tau = \omega_{\parallel} / v_0$

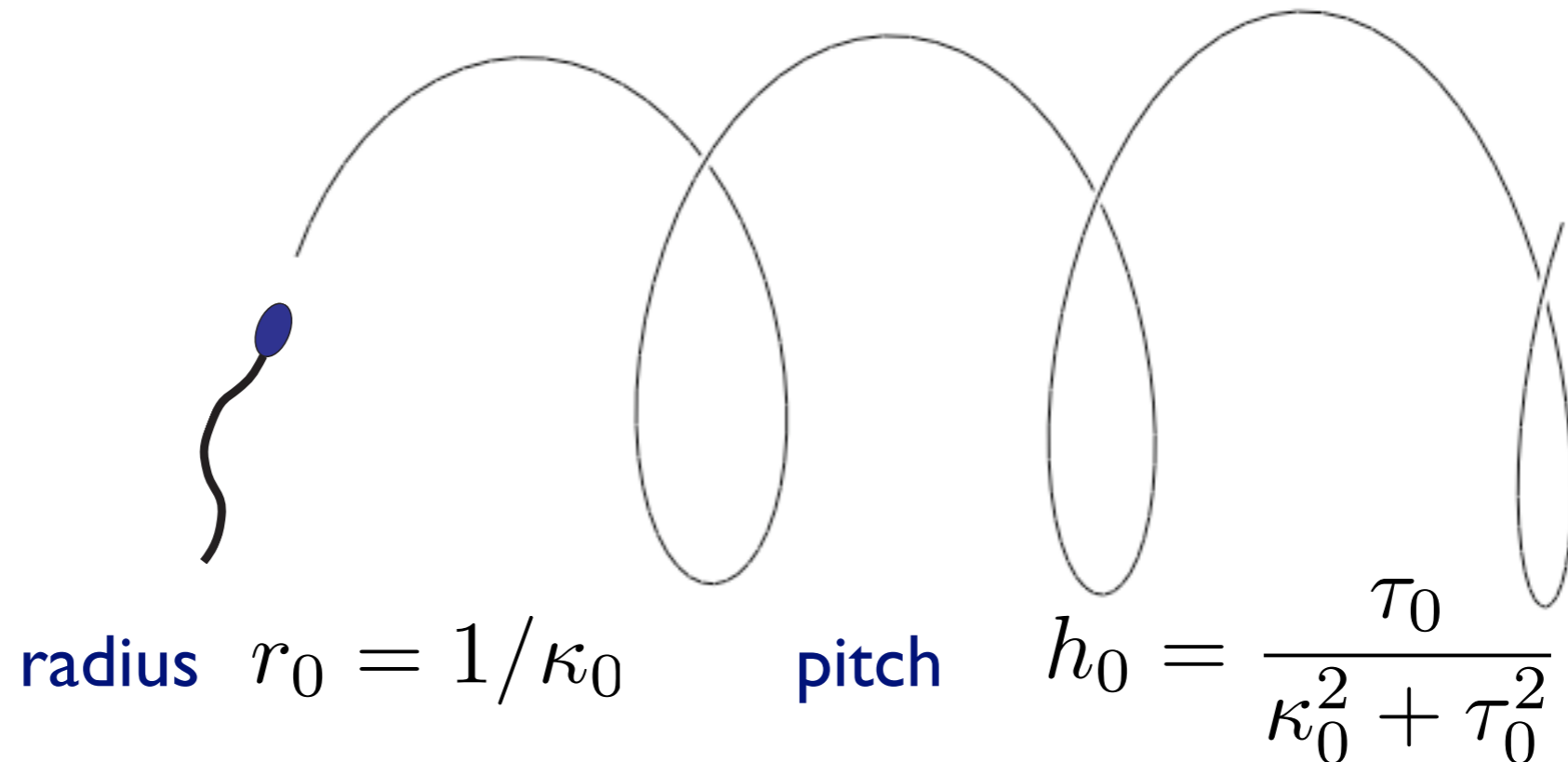
Chiral swimmers



helical
swimming path

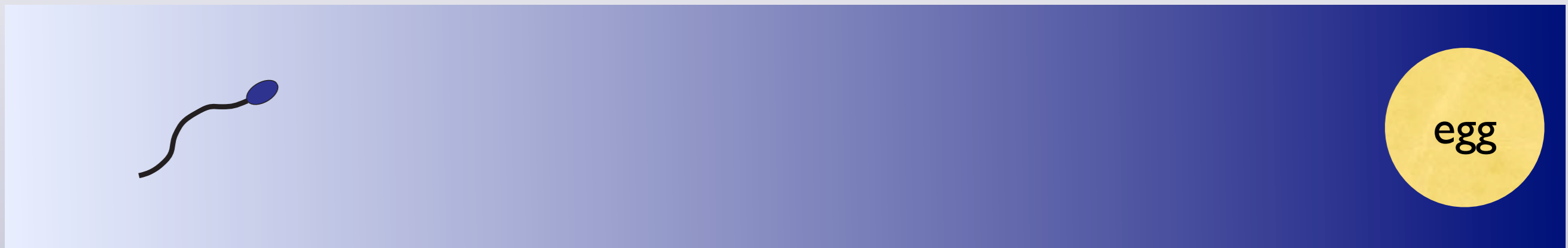
curvature κ_0

torsion τ_0

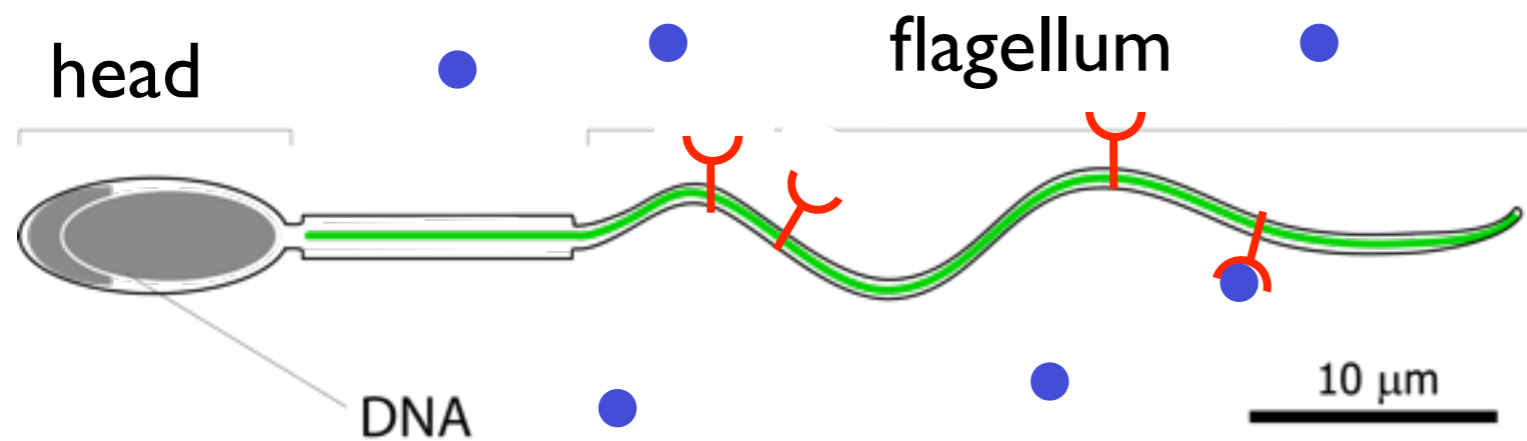


Cilium as sensory antennae

Chemical gradient guides sperm to the egg



Motility controlled by chemical signals



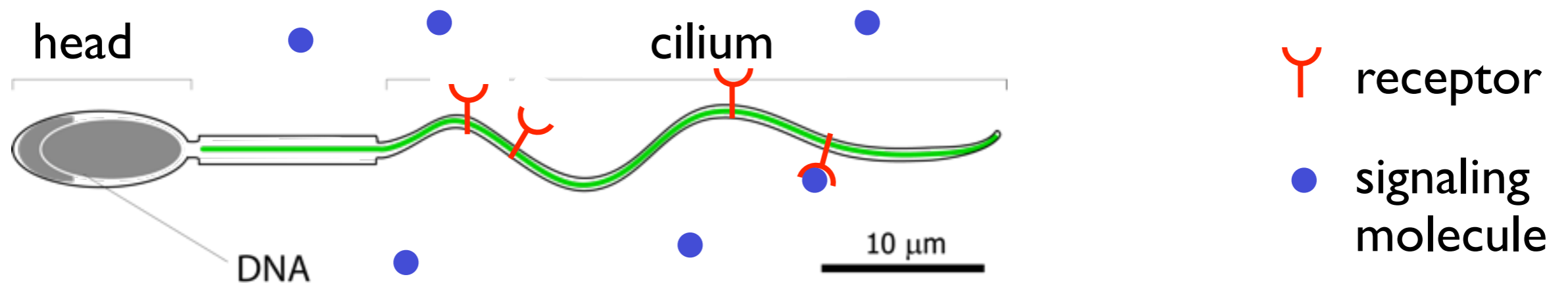
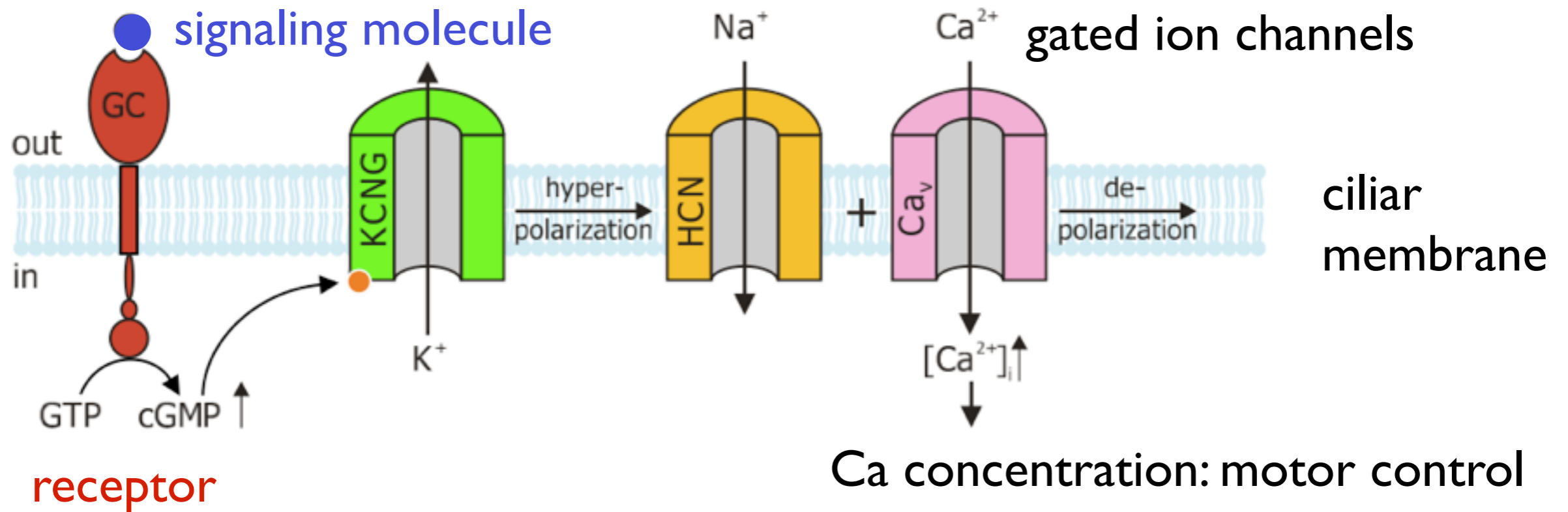
receptor



chemoattractant molecule



Signaling system



Steering towards a chemical signal

Experiments: optical uncaging of chemoattractant



Sea urchin sperm

Sperm swim towards
high concentration
of chemoattractant

Single molecule
detection

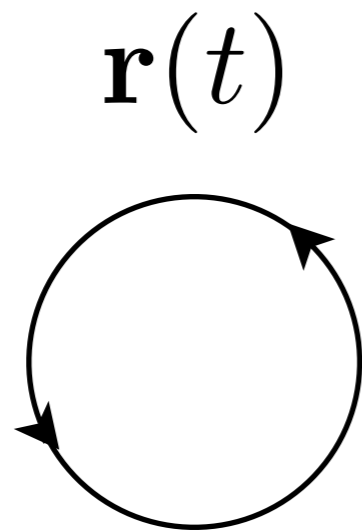
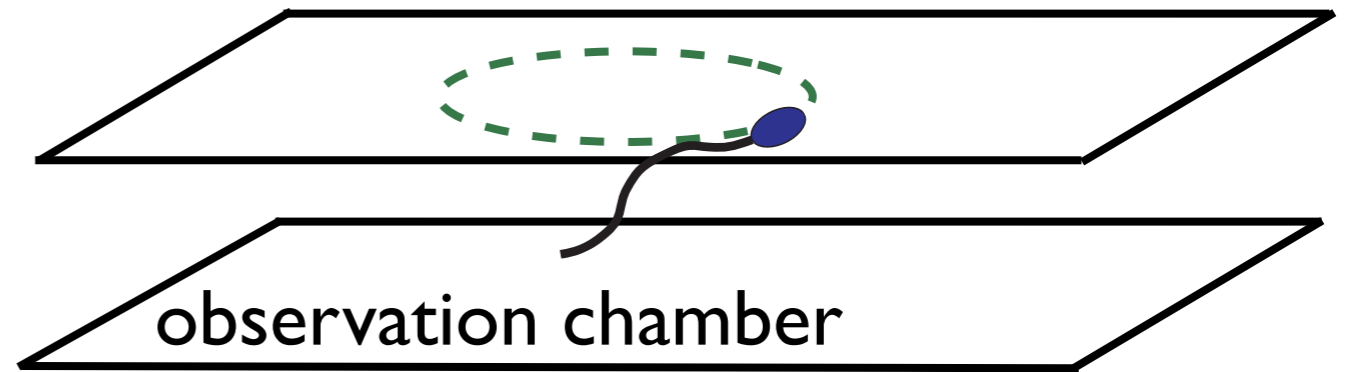
L. Dai, L. Alvarez, U.B. Kaupp, caesar research center, Bonn

Böhmer et al. EMBO J. (2005)

Confinement: planar geometry

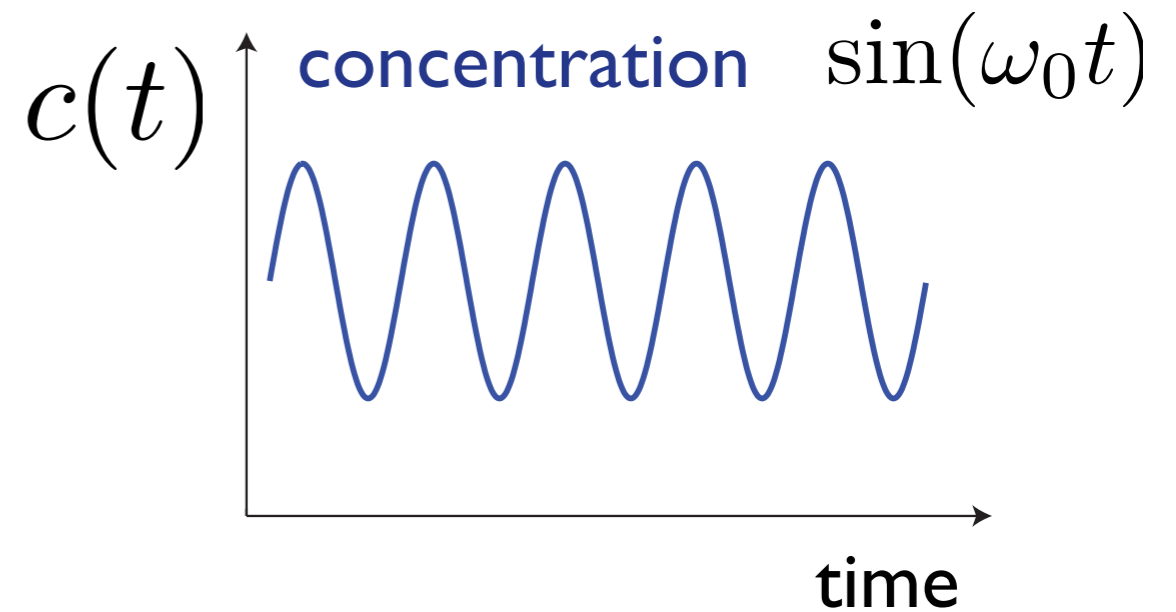
Swimming on circular paths

$$\kappa_0 = 1/r_0$$



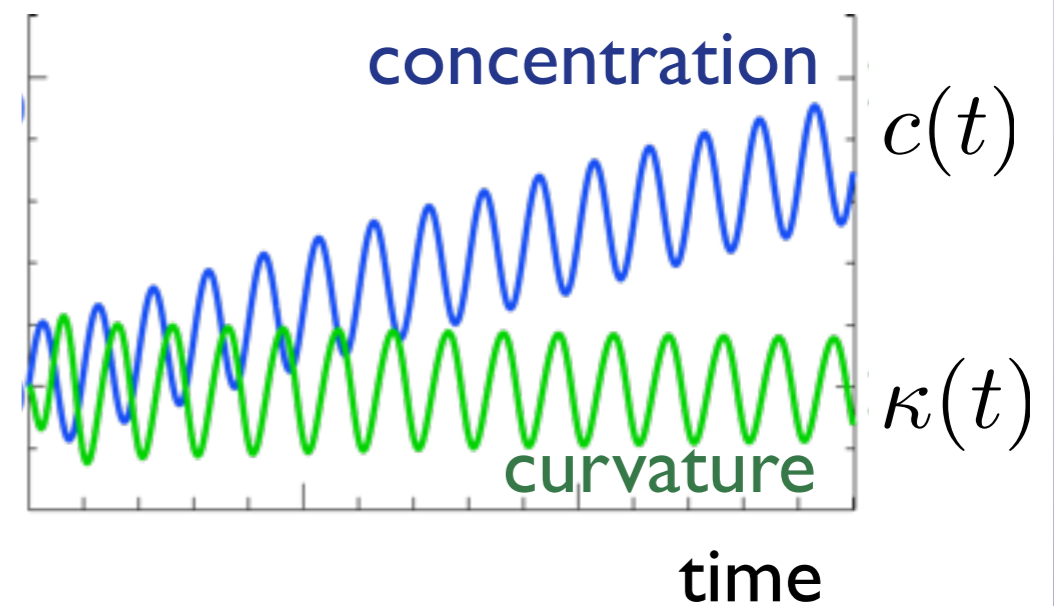
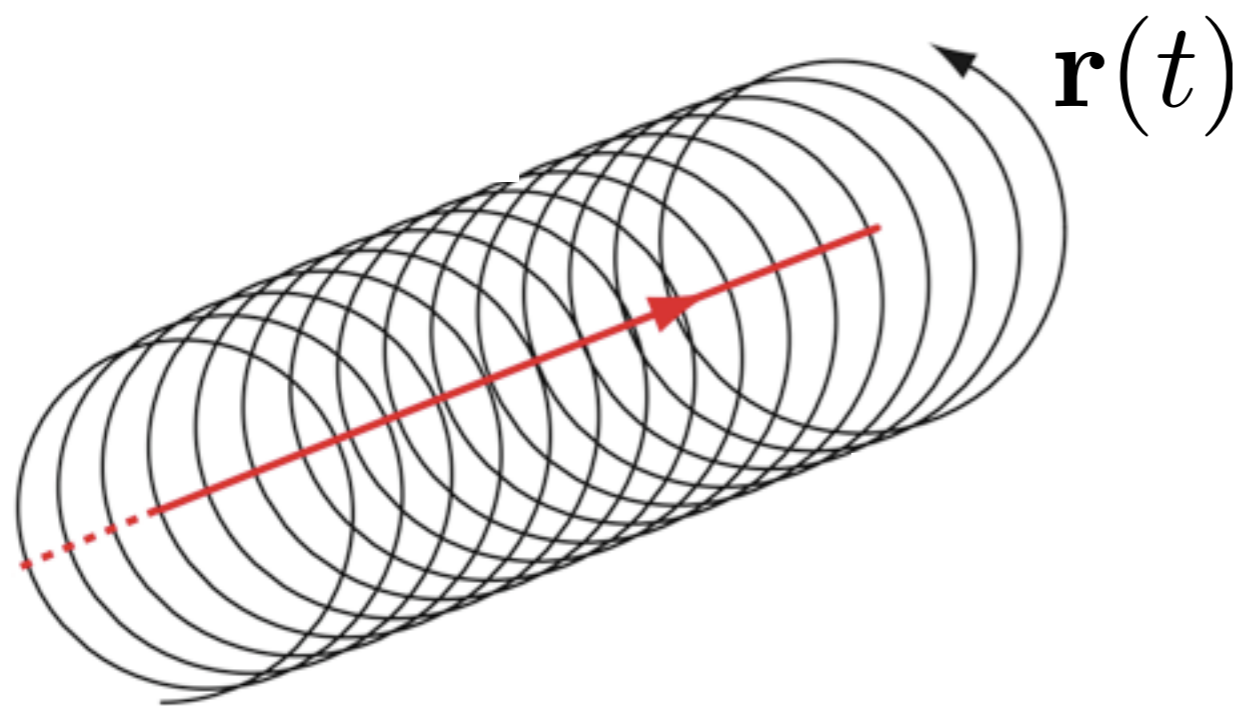
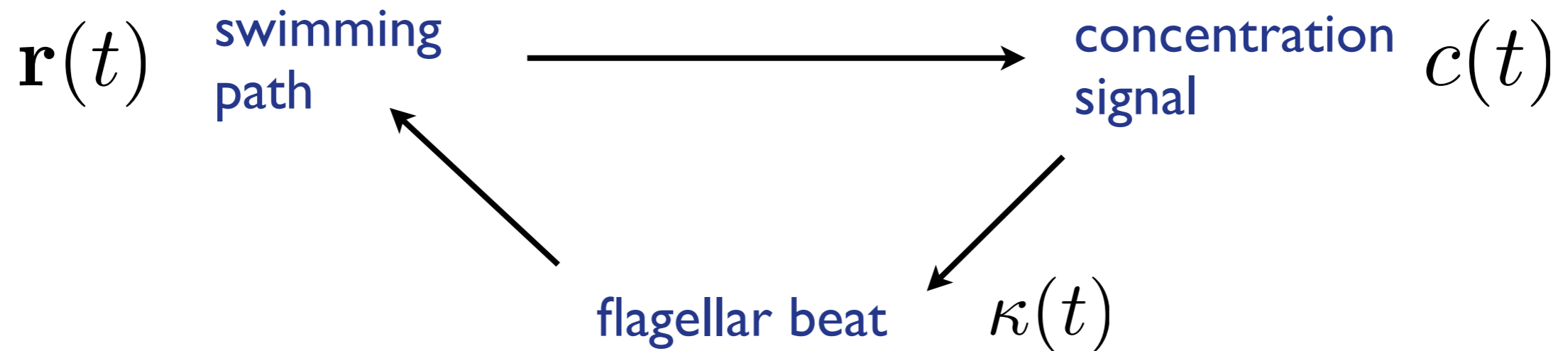
constant curvature

$$\omega_0 = v_0 \kappa_0$$

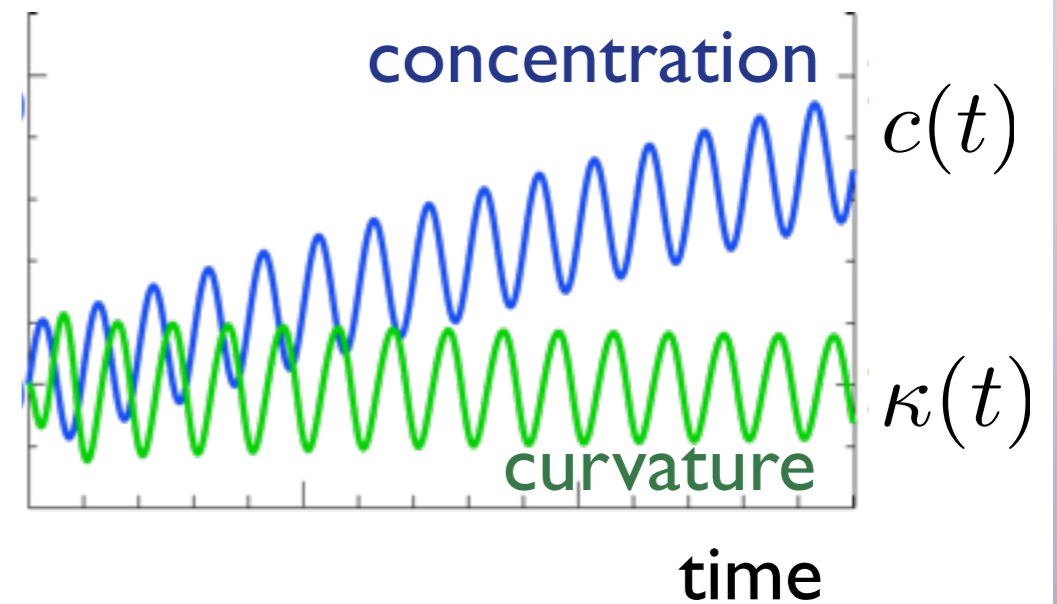
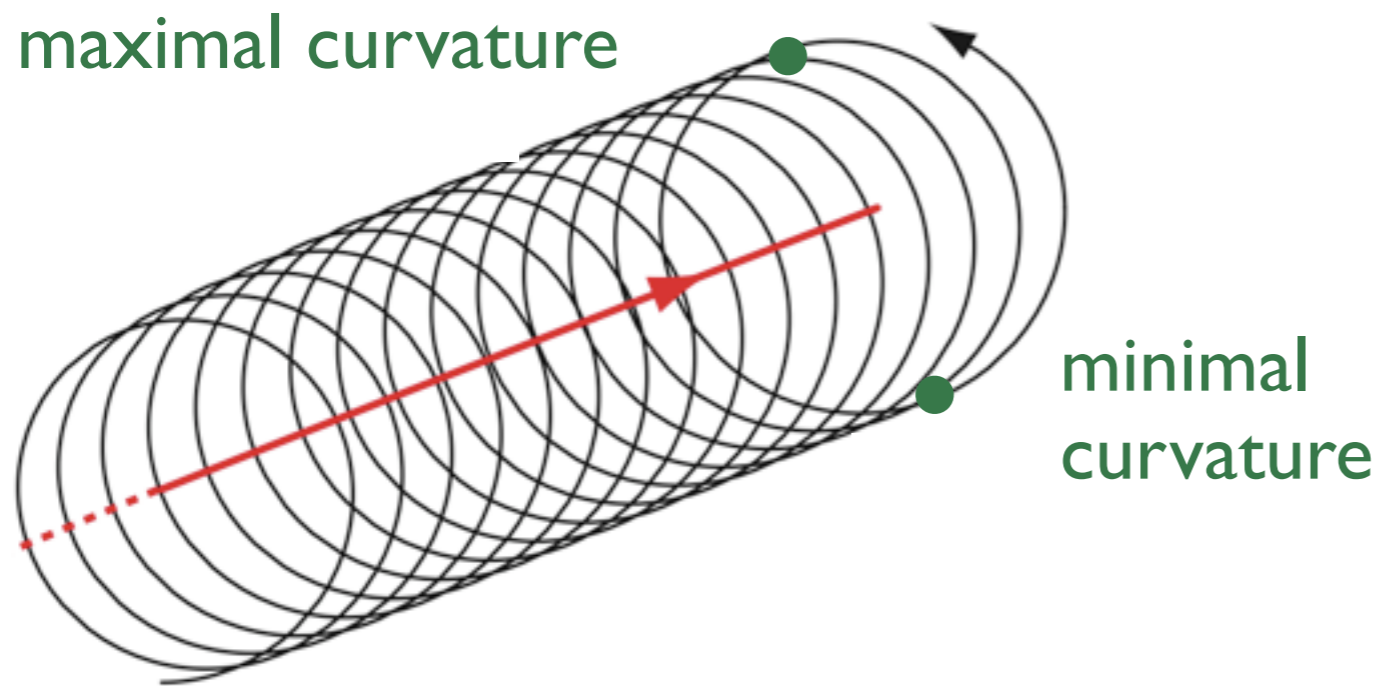
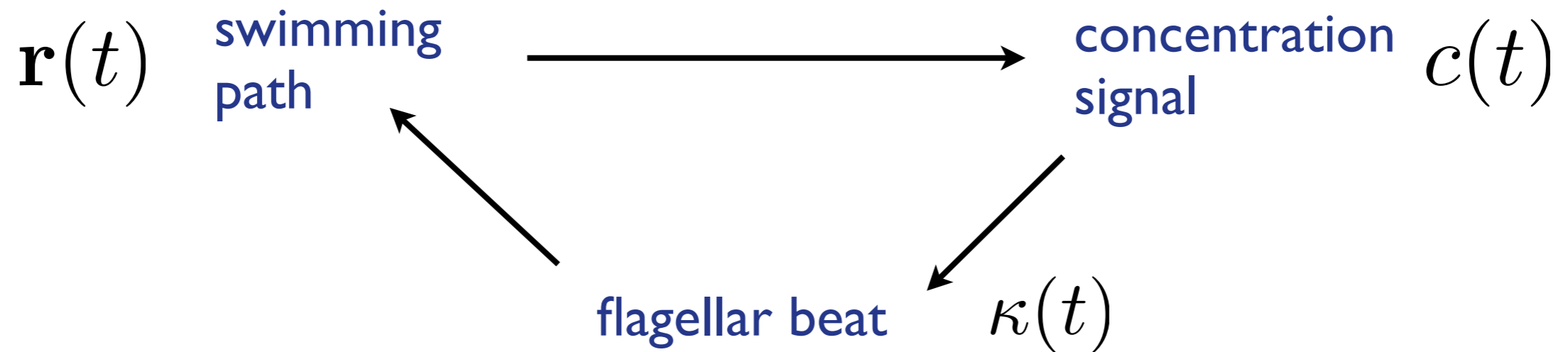


concentration gradient

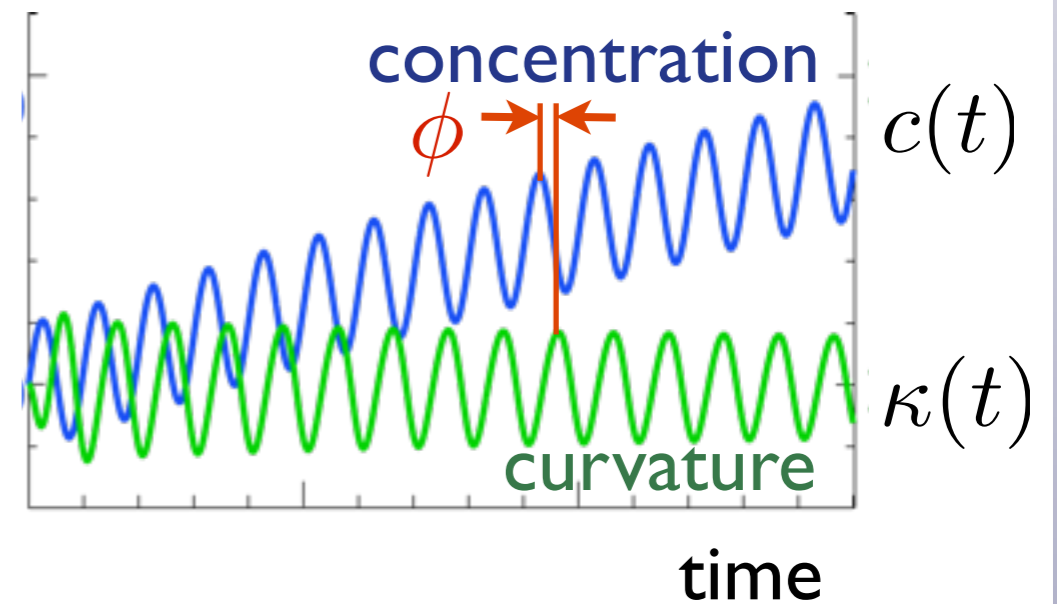
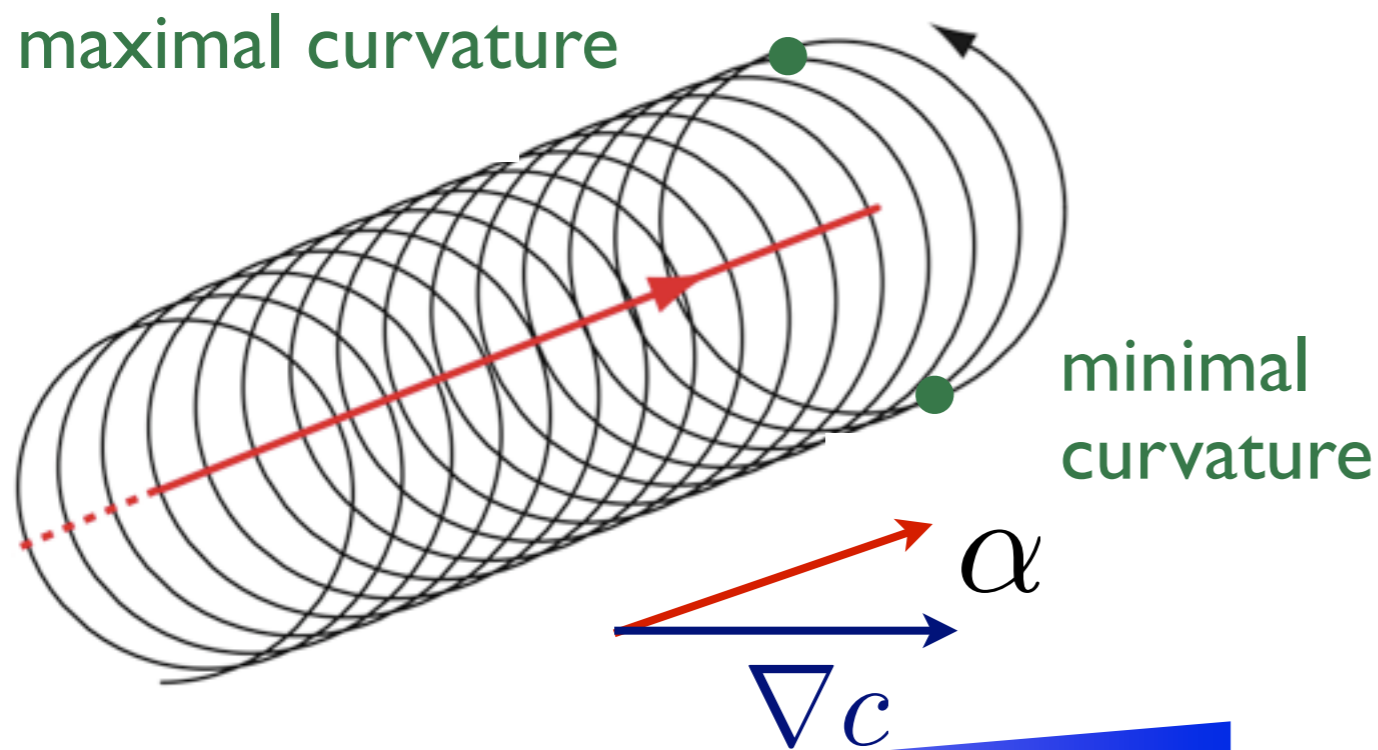
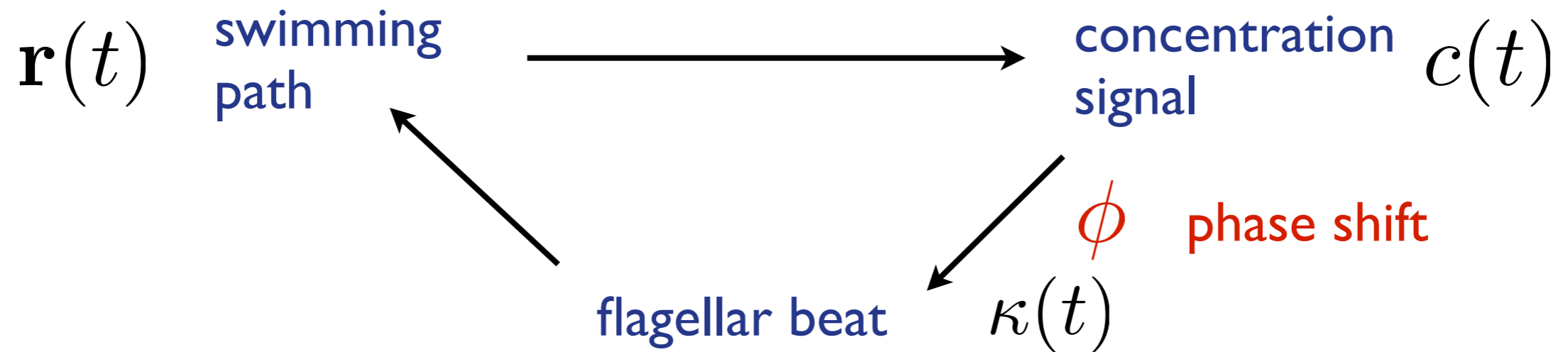
Steering in the plane



Steering in the plane

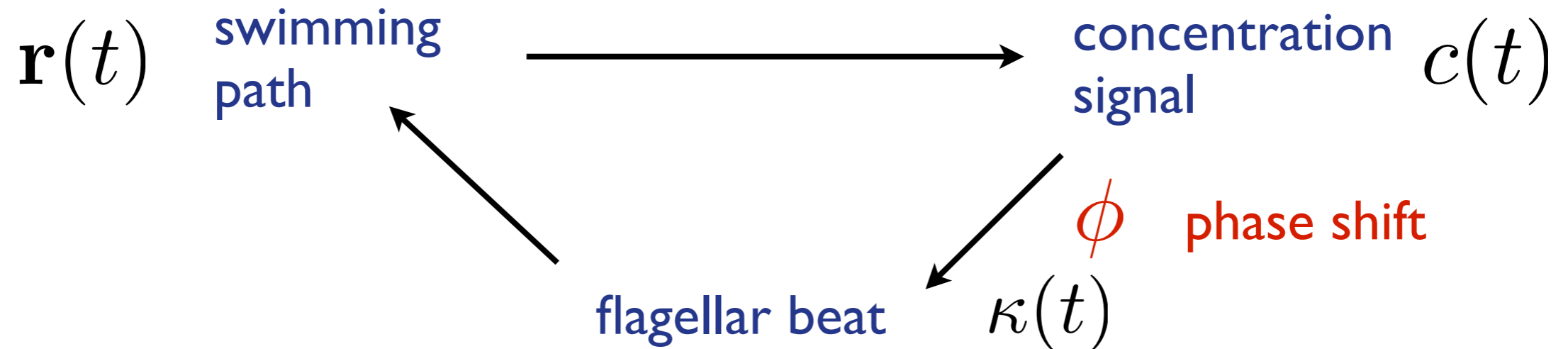


Steering in the plane



$$\alpha = \frac{3\pi}{2} - \phi$$

Signaling in linear response



linear response function

adaptation

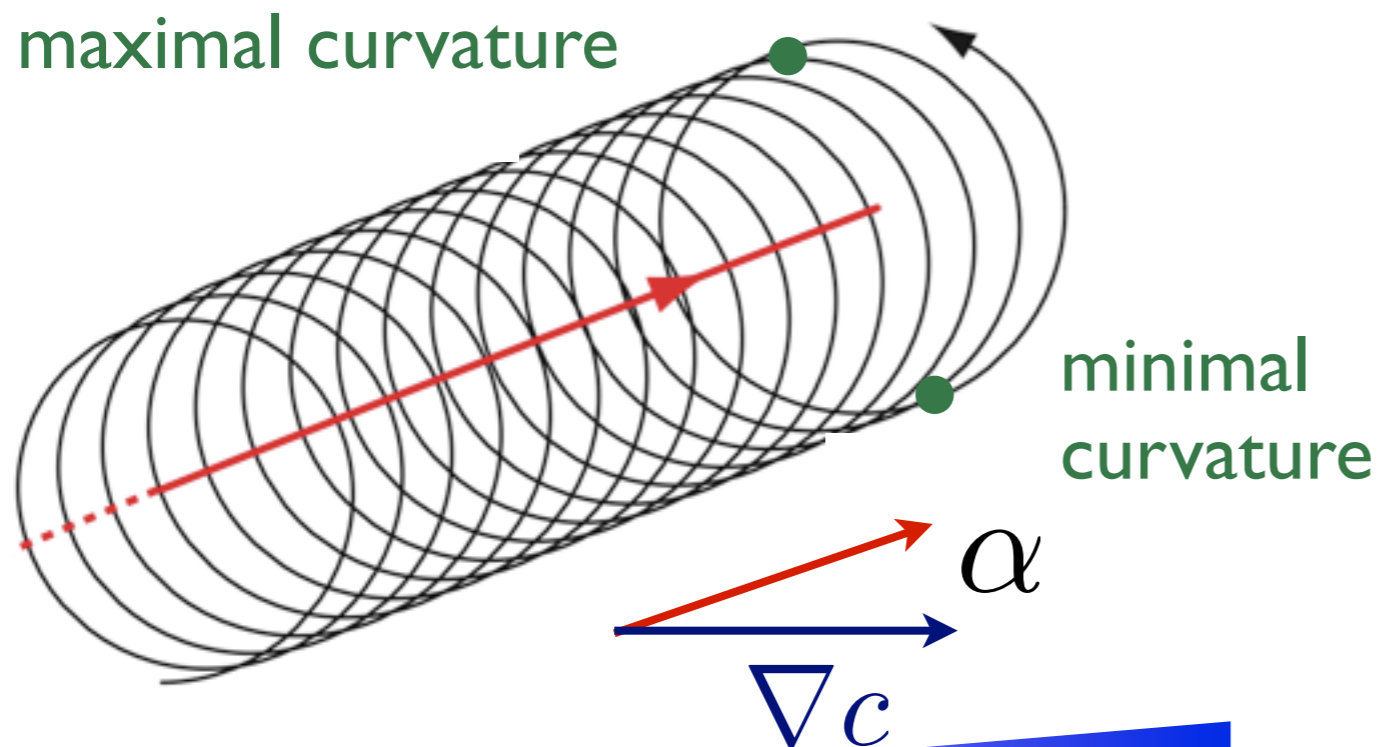
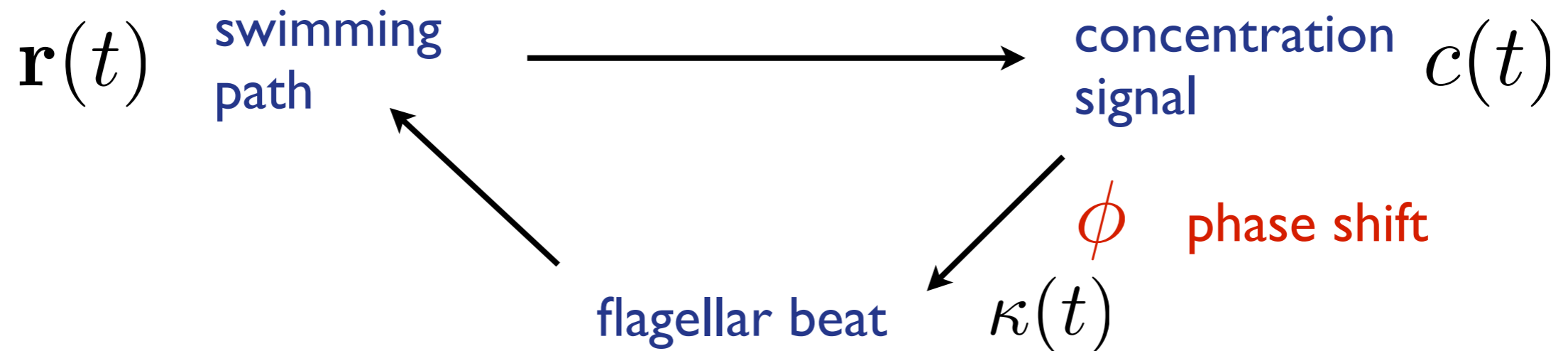
$\Delta c/c$

$$\tilde{\kappa}(\omega) = \chi_{\kappa}(\omega) \tilde{c}(\omega)$$

$$\chi_{\kappa} = \rho e^{i\phi}$$

$$\rho \sim 1/c$$

Steering in the plane



$$\chi_{\kappa}(\omega_0) = \rho e^{i\phi}$$

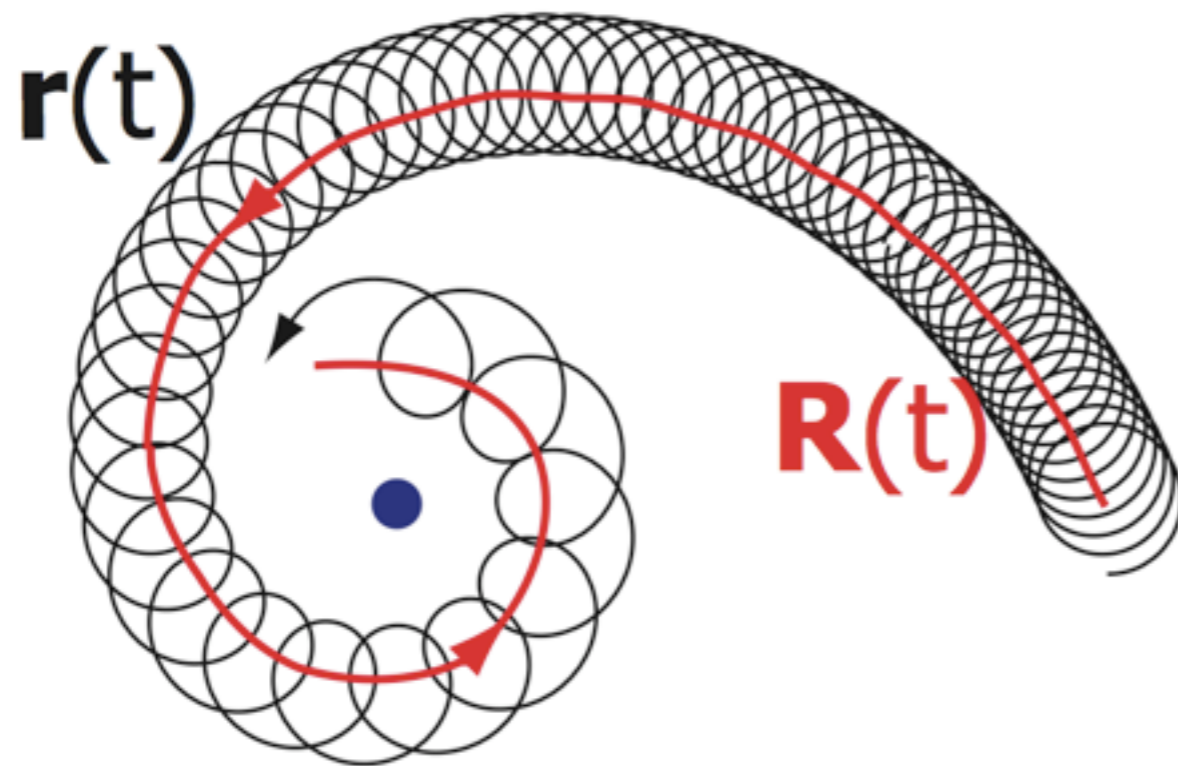
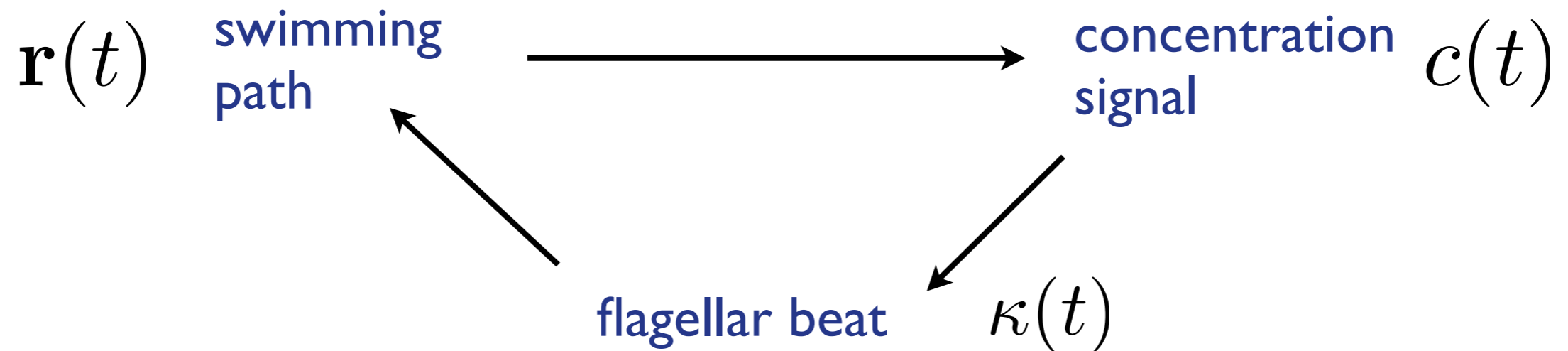
$$v_d \simeq \frac{1}{2} v_0 r_0^2 \rho |\nabla c|$$

$$\alpha = \frac{3\pi}{2} - \phi$$

chemotaxis: $-\frac{\pi}{2} < \alpha < \frac{\pi}{2}$

$$\chi'_{\kappa} < 0$$

Steering in the plane



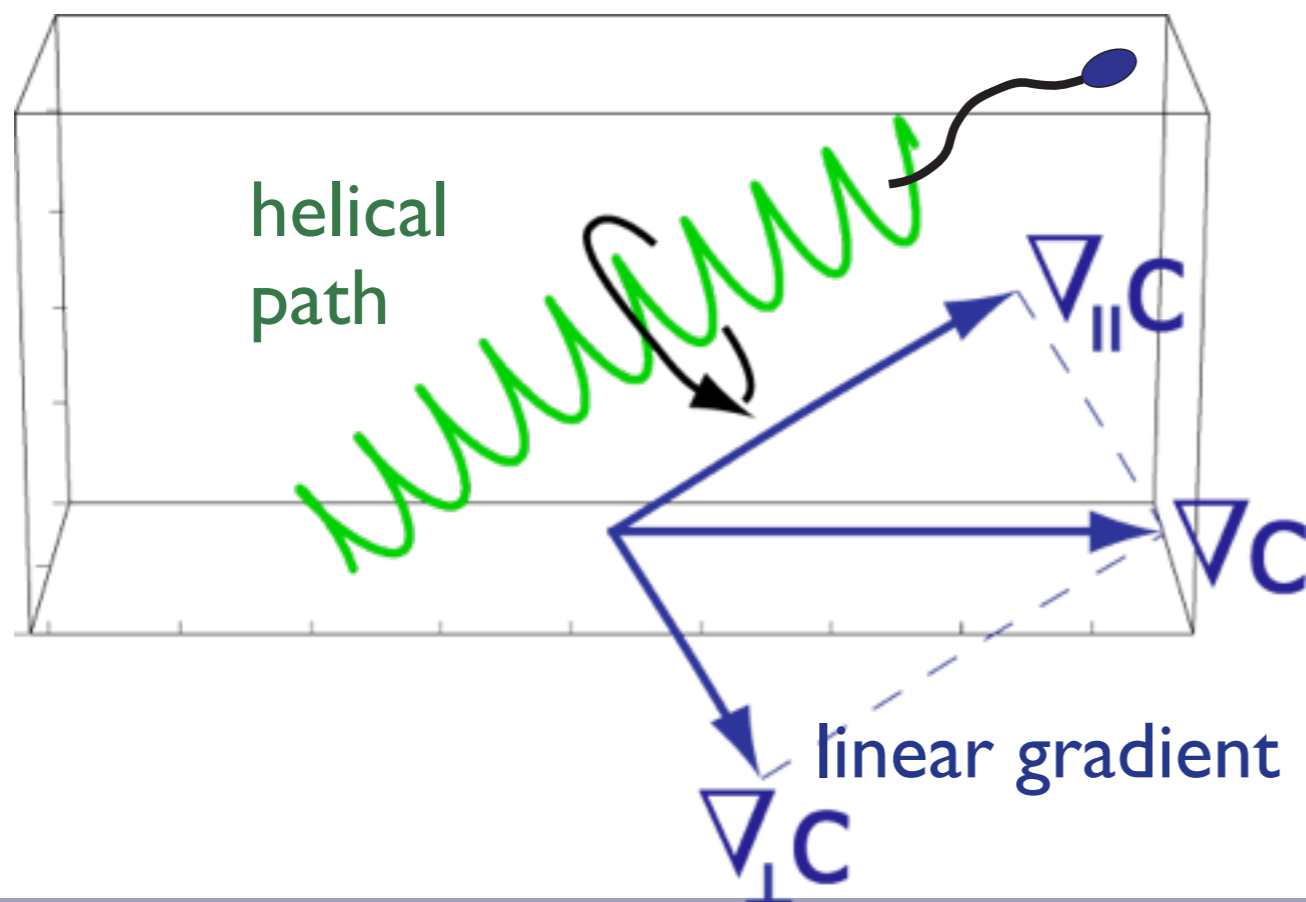
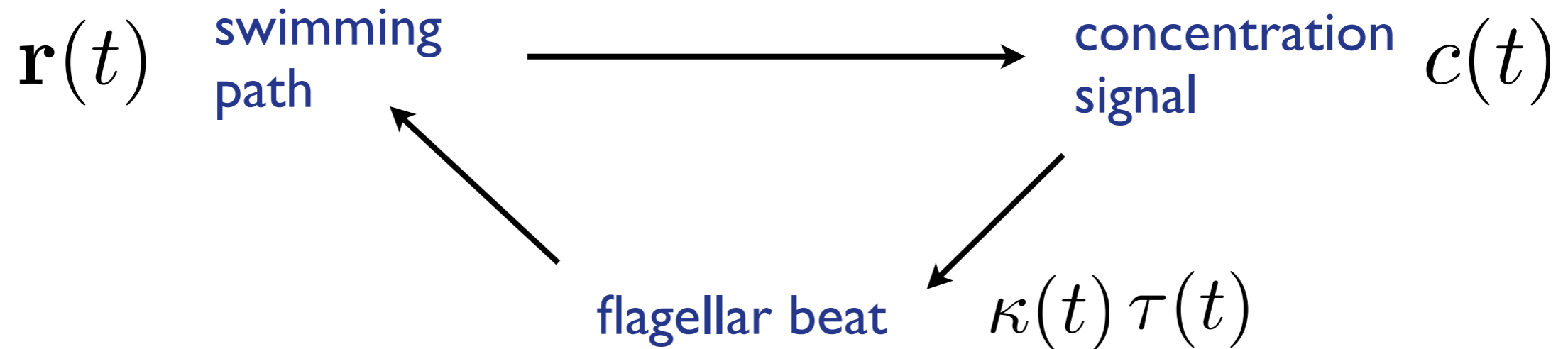
radial concentration field
spiralling motion to the center

$$\alpha = \frac{3\pi}{2} - \phi$$

chemotaxis: $-\frac{\pi}{2} < \alpha < \frac{\pi}{2}$

$$\chi'_{\kappa} < 0$$

Motion in 3-d space



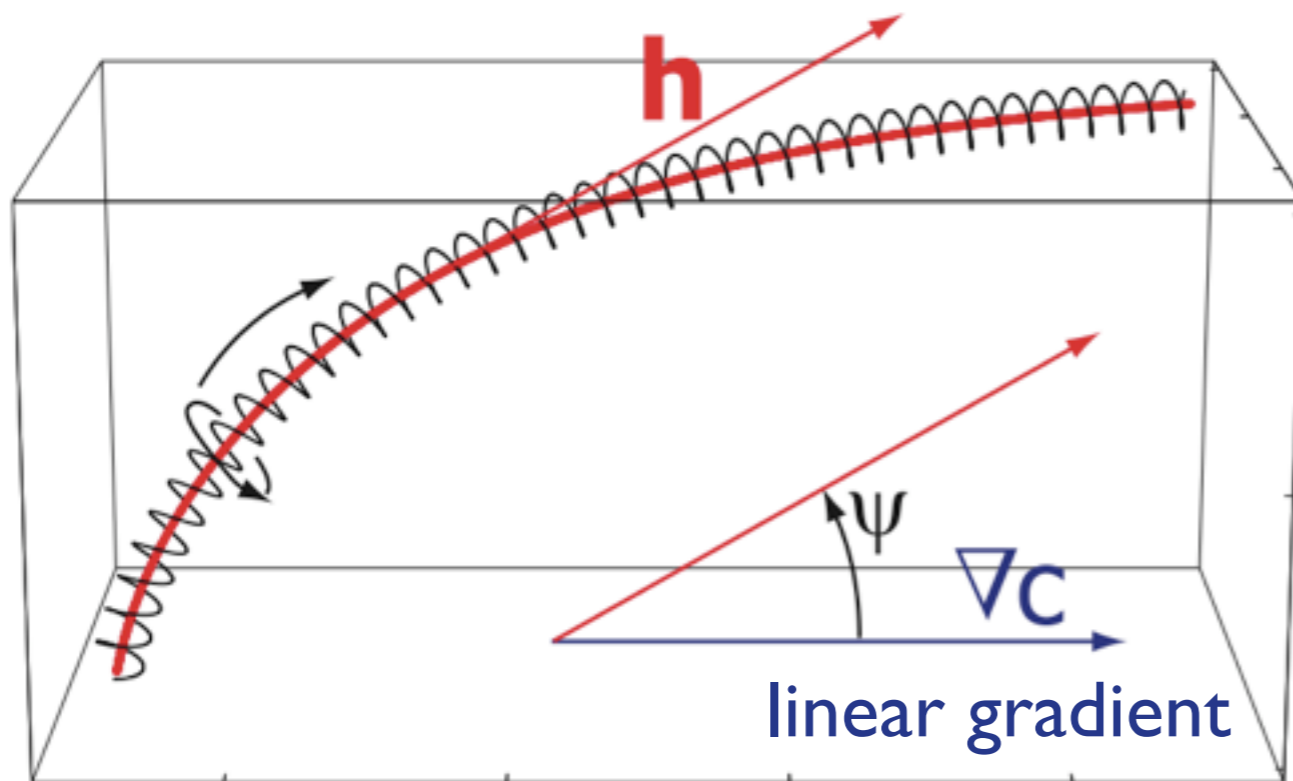
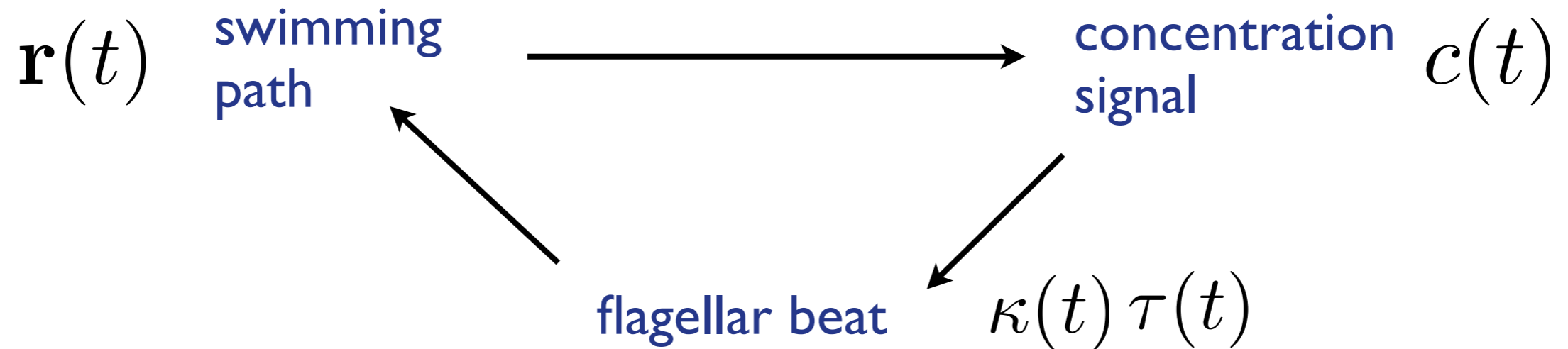
periodic concentration signal

$$c(t) \simeq R \nabla_{\perp} c \sin(\omega t)$$

periodic modulation of κ
 τ

$$\chi_{\kappa}(\omega) \quad \chi_{\tau}(\omega)$$

Motion in 3-d space



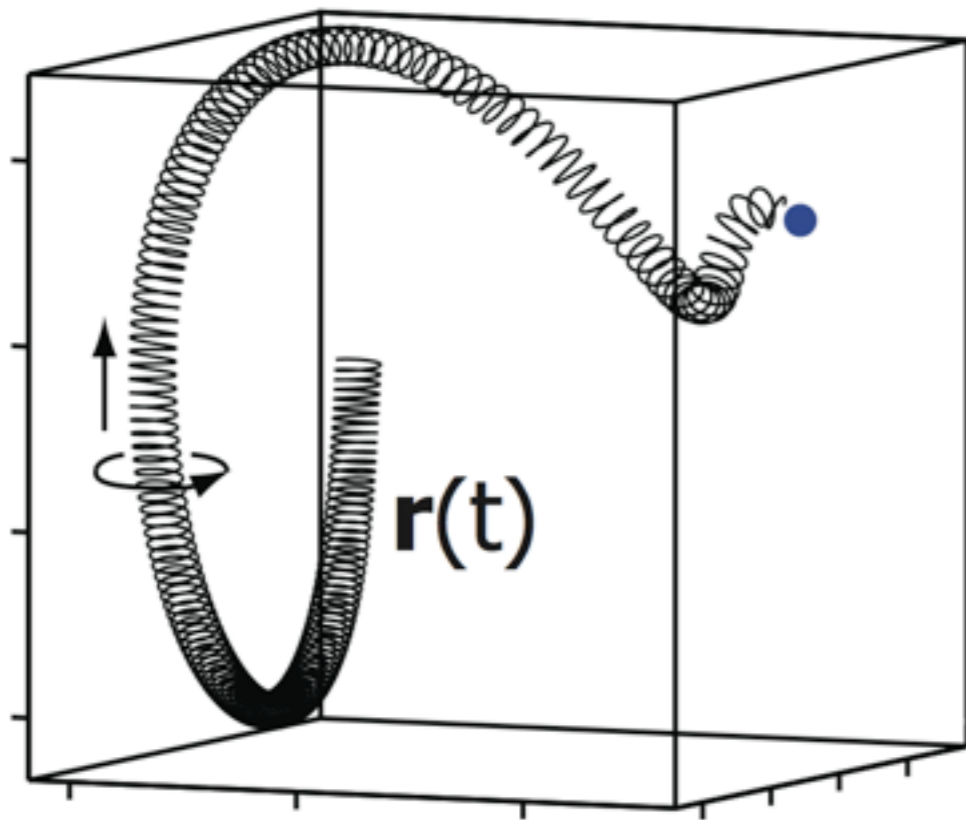
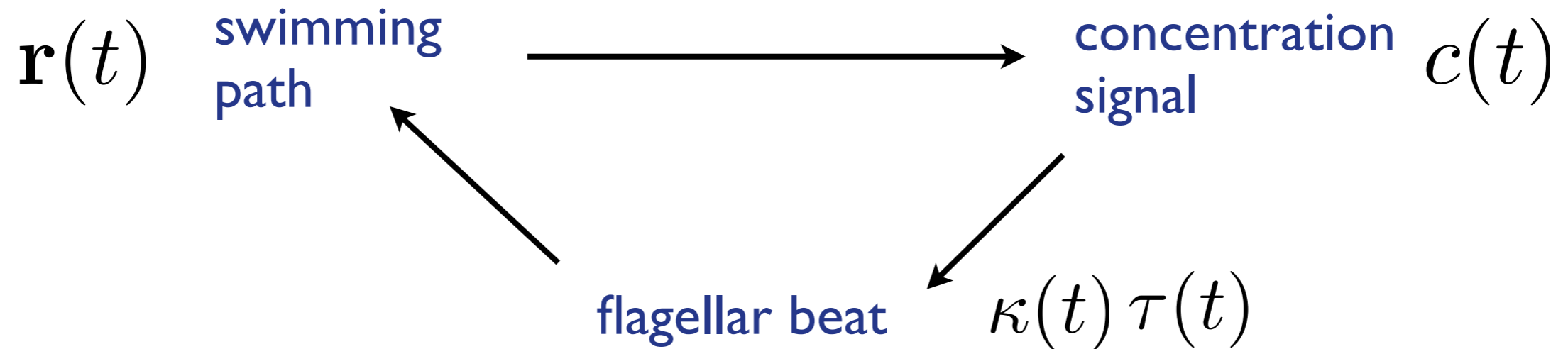
Helix bending

$$\dot{\psi} = -\beta \sin \psi$$

$$\beta = (\epsilon_{\tau} \chi'_{\tau} - \epsilon_{\kappa} \chi'_{\kappa}) |\nabla c|$$

$$\epsilon_{\kappa} = \omega_0 r_0 h_0 / 2 \quad \epsilon_{\tau} = \omega_0 r_0^2 / 2$$

Radial concentration in 3-d

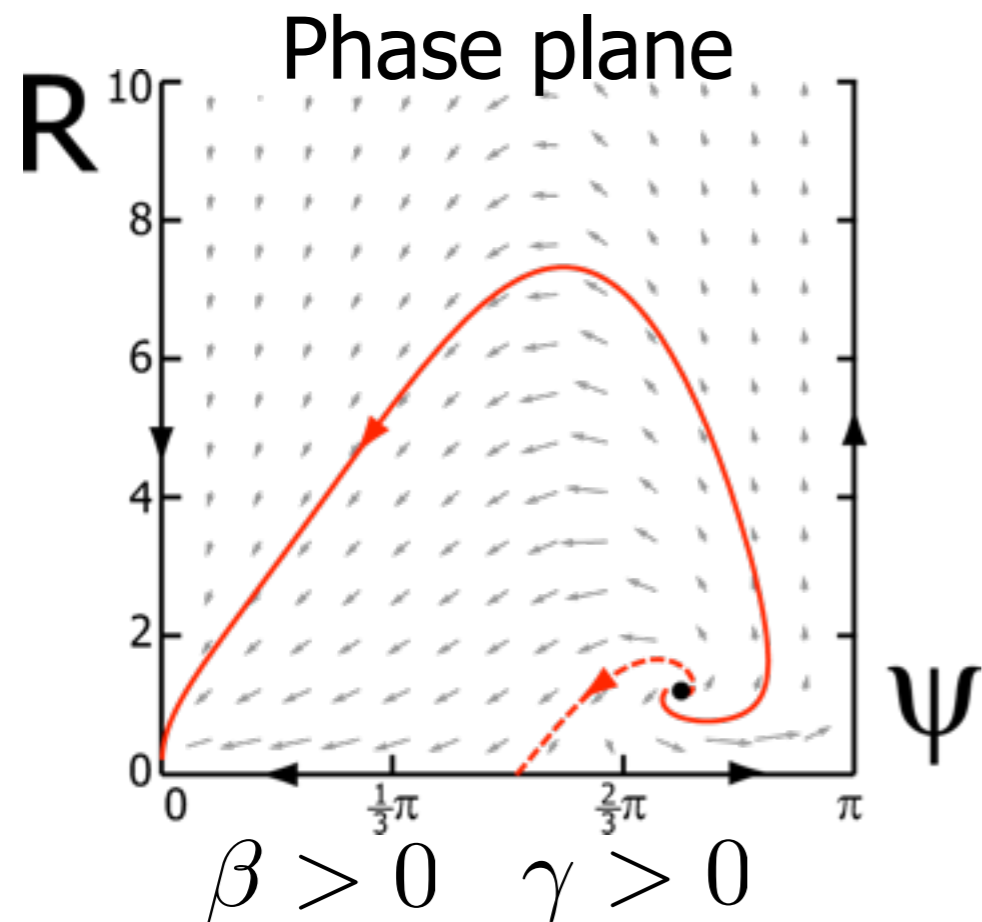
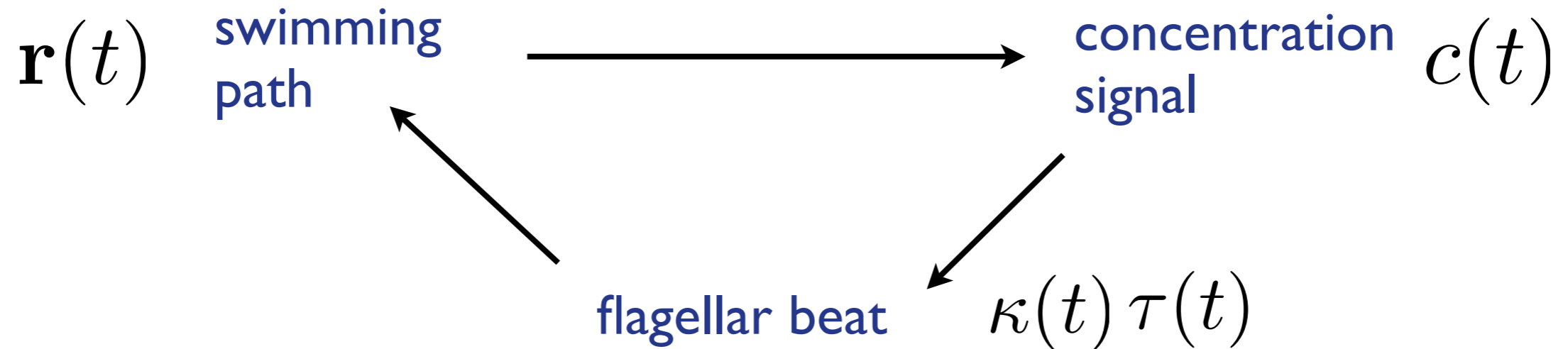


Nonlinear dynamics on superhelical swimming paths

$$\dot{R} = -\omega h \cos \psi - \gamma \sin^2 \psi$$

$$\dot{\psi} = -\sin \psi \left(\beta - \frac{1}{R} (\omega h - \gamma \cos \psi) \right)$$

Radial concentration in 3-d



Nonlinear dynamics on superhelical swimming paths

$$\dot{R} = -\omega h \cos \psi - \gamma \sin^2 \psi$$

$$\dot{\psi} = -\sin \psi \left(\beta - \frac{1}{R} (\omega h - \gamma \cos \psi) \right)$$

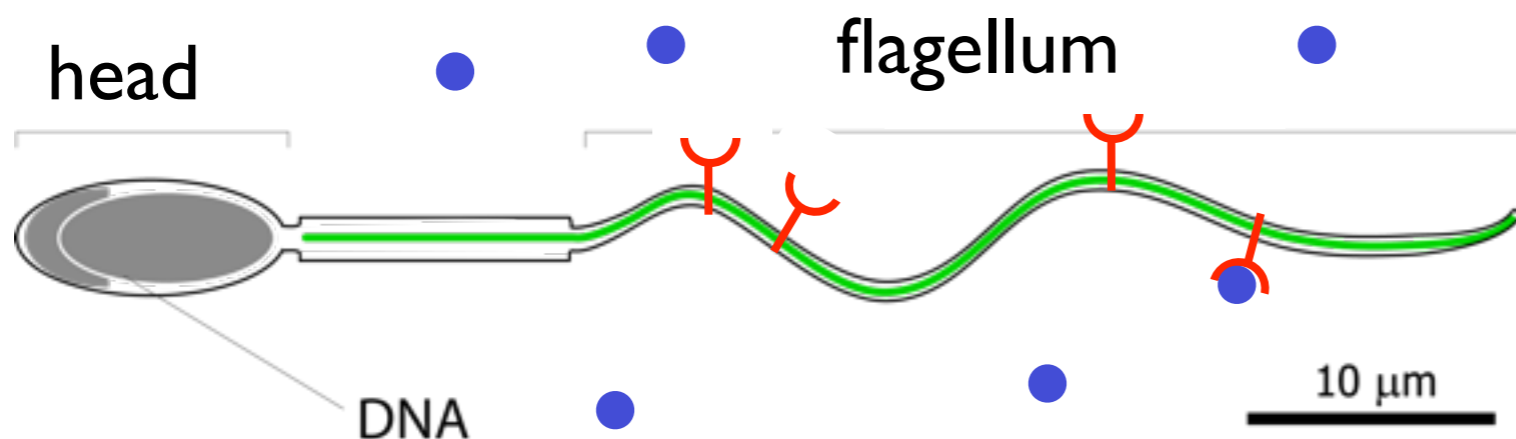
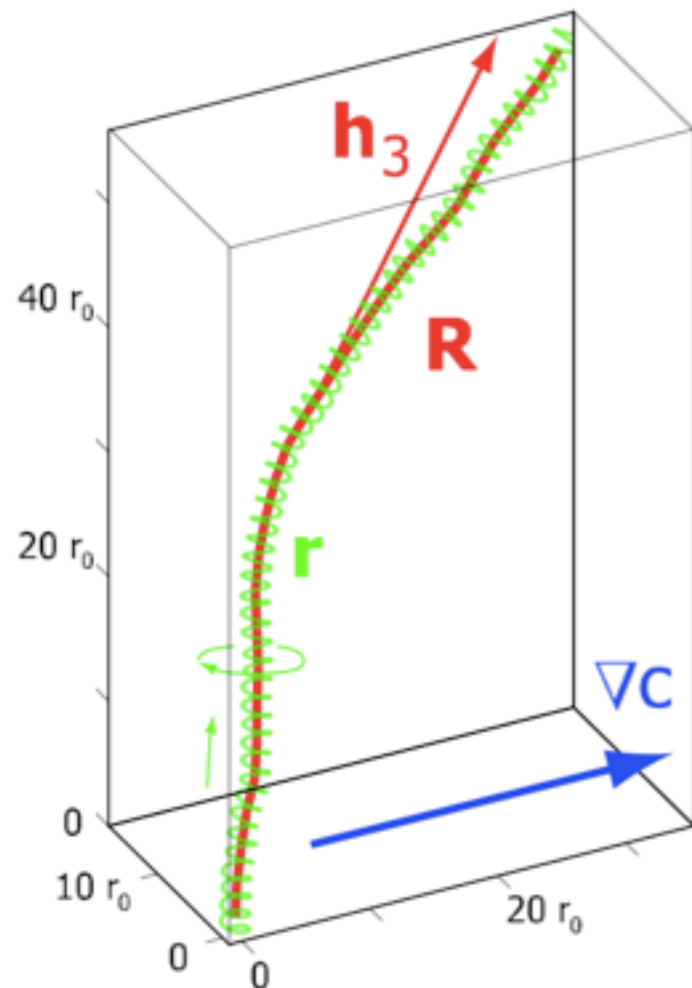
Shot noise

Single molecule detection

$$c(t) = \sum_n \delta(t - t_n)$$

Stochastic differential geometry

Robust steering: drift + diffusion



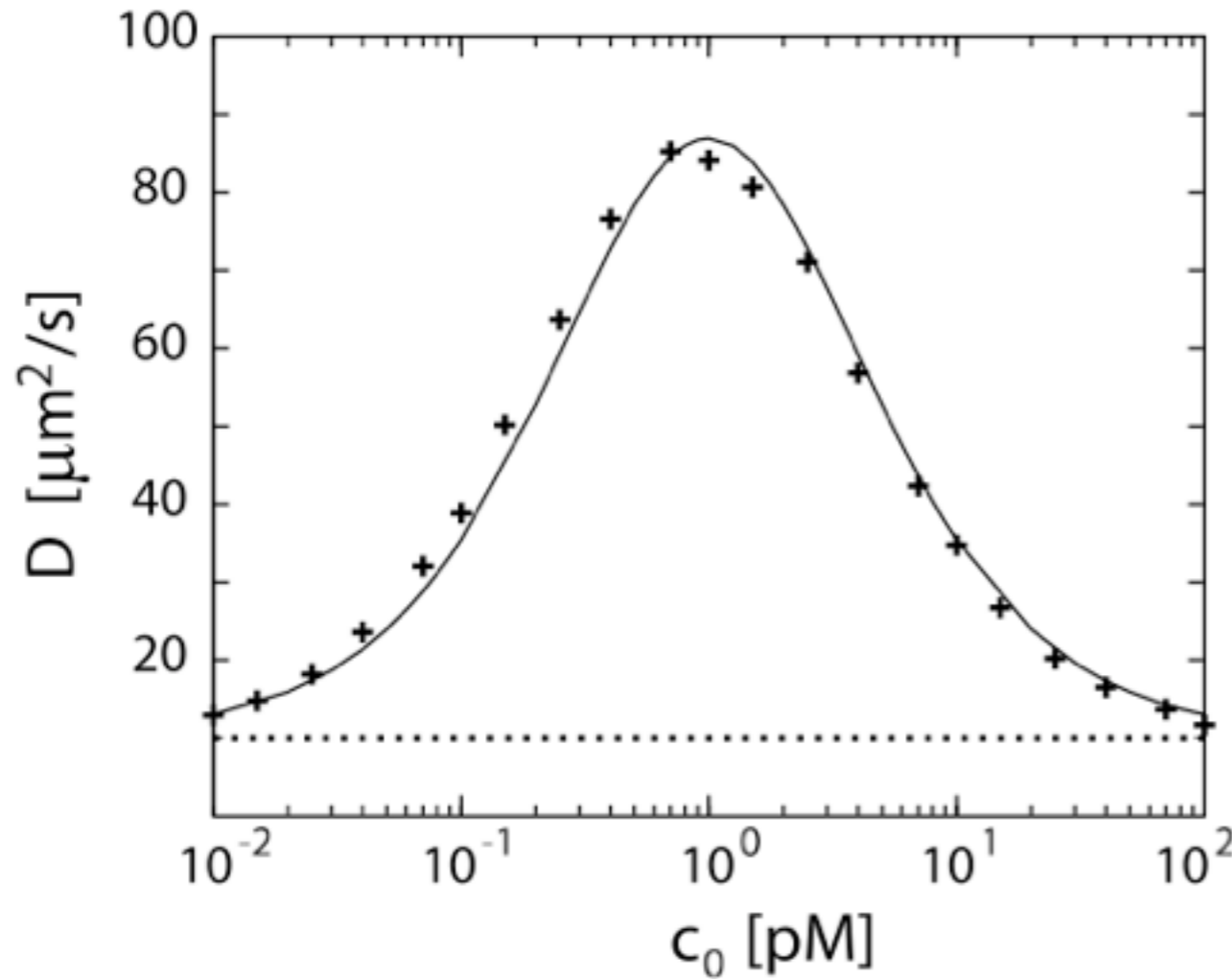
receptor



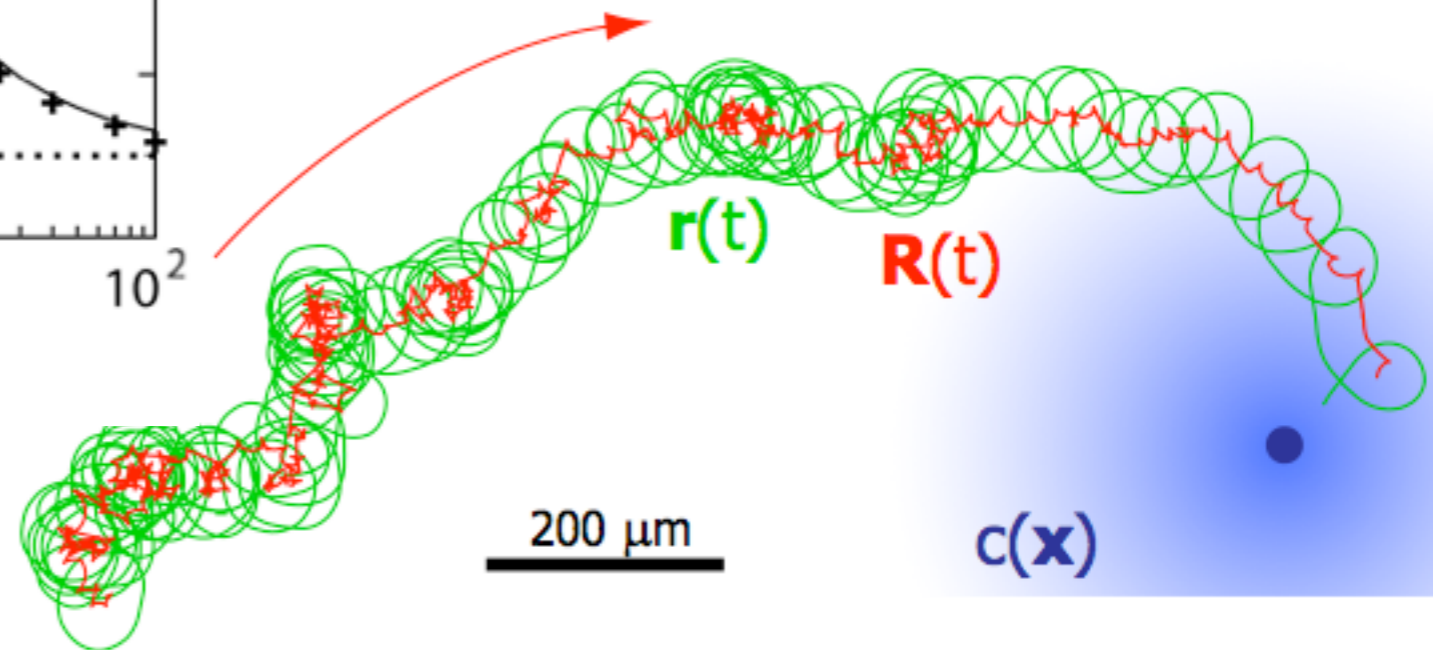
chemoattractant molecule

Shot noise

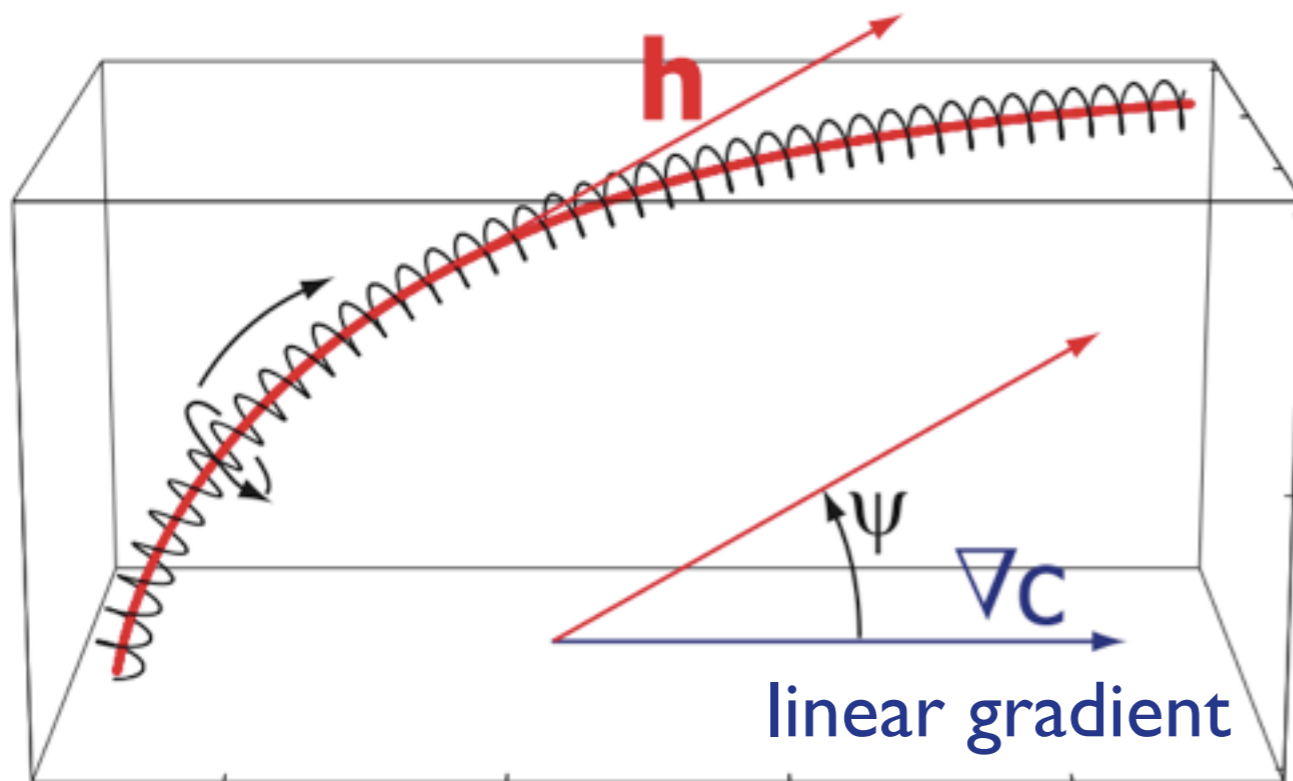
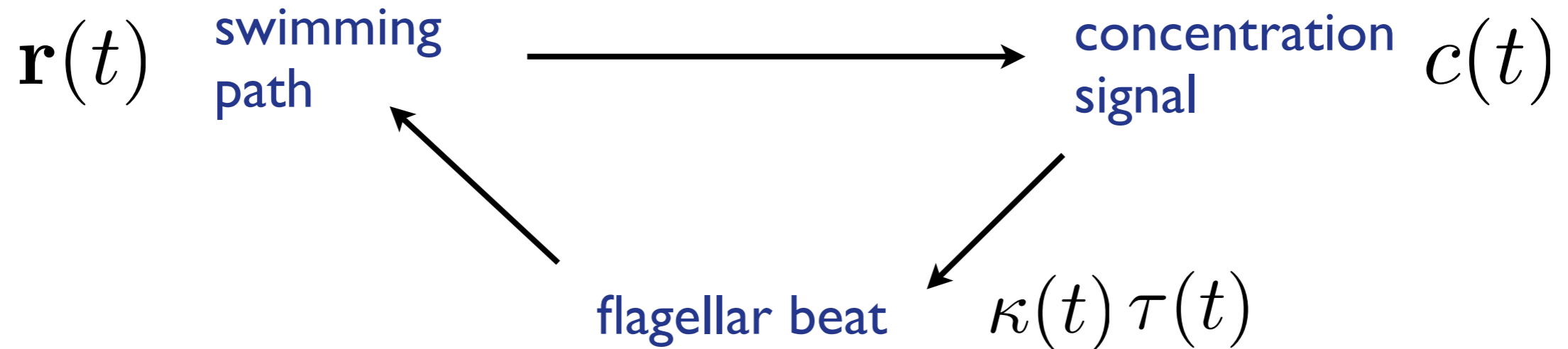
Stochastic simulations of chemotaxis



$$D = r_0^2 v_0^2 \tilde{S}_\kappa(\omega_0) / 4$$



Chemotaxis with noise



Helix bending

$$\dot{\psi} = -\beta \sin \psi + D \cot \psi + \xi$$

noise-induced drift

noise

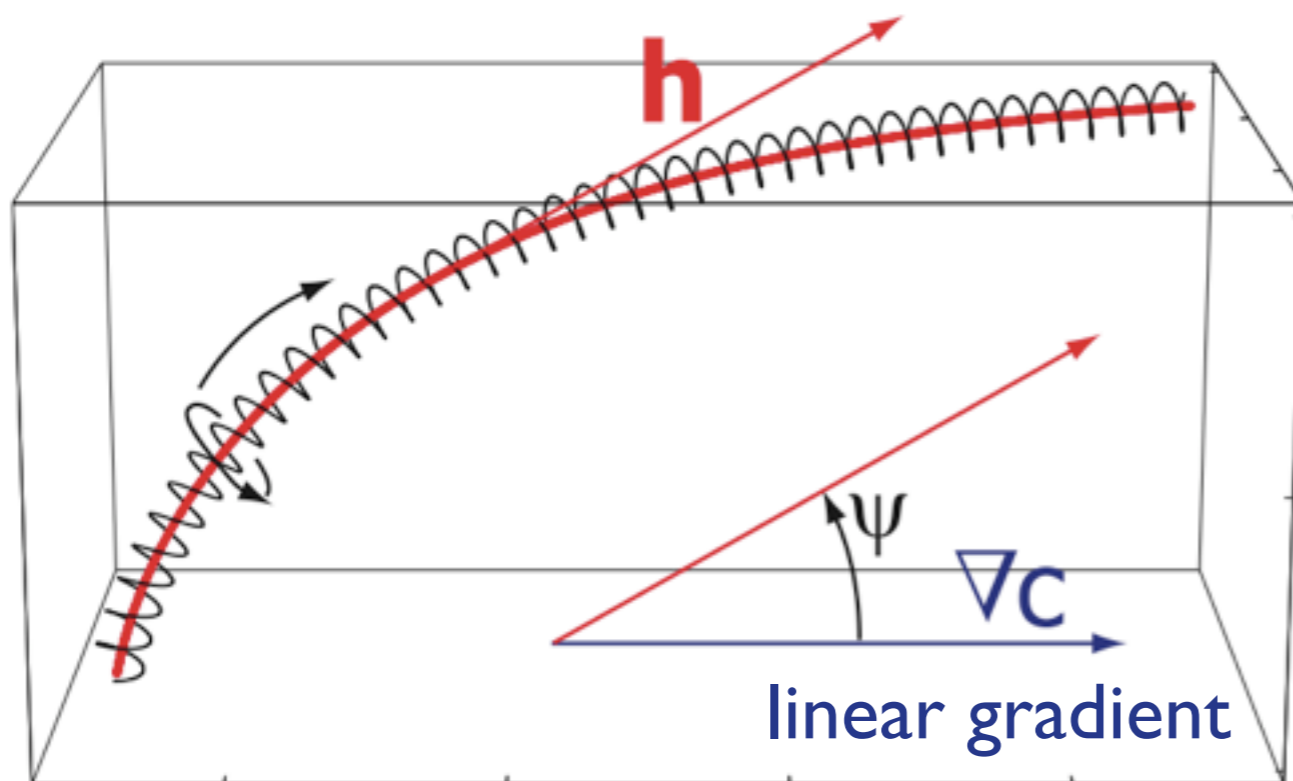
Chemotaxis with noise

Noise strength

$$D = \omega_0^2 (h_0^2 \tilde{S}_\kappa(\omega_0) + r_0^2 \tilde{S}_\tau(\omega_0) - 2r_0 h_0 \tilde{S}_{\kappa,\tau}(\omega_0)) / 2$$

Persistence time

$$t_P = (2D)^{-1}$$



Helix bending

$$\dot{\psi} = -\beta \sin \psi + D \cot \psi + \xi$$

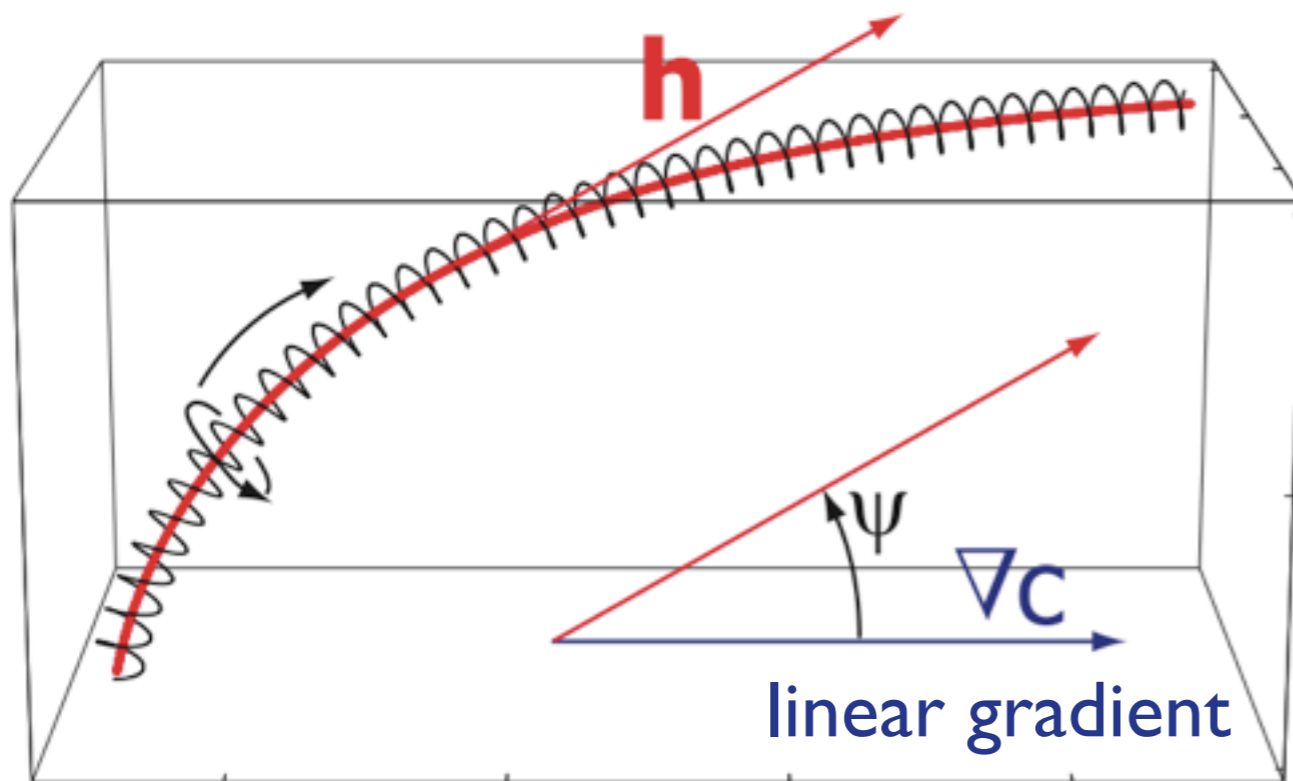
noise-induced drift

noise

Chemotaxis with noise

$$P_0(\cos \psi) \sim \exp(\cos \psi \beta / D)$$

$$\langle \cos \psi \rangle = \coth\left(\frac{\beta}{D}\right) + \frac{D}{\beta}$$



Helix bending

$$\dot{\psi} = -\beta \sin \psi + D \cot \psi + \xi$$

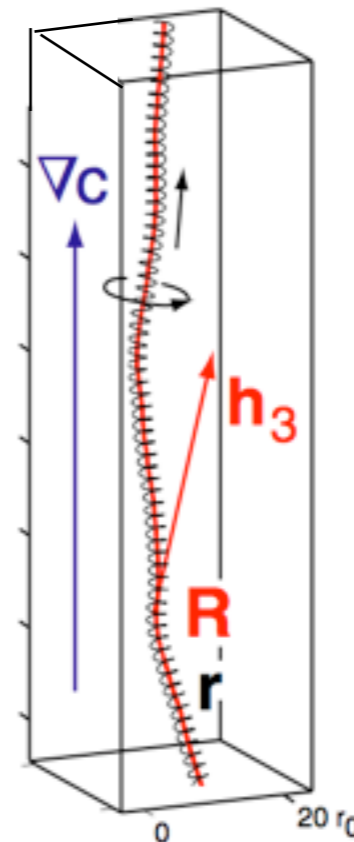
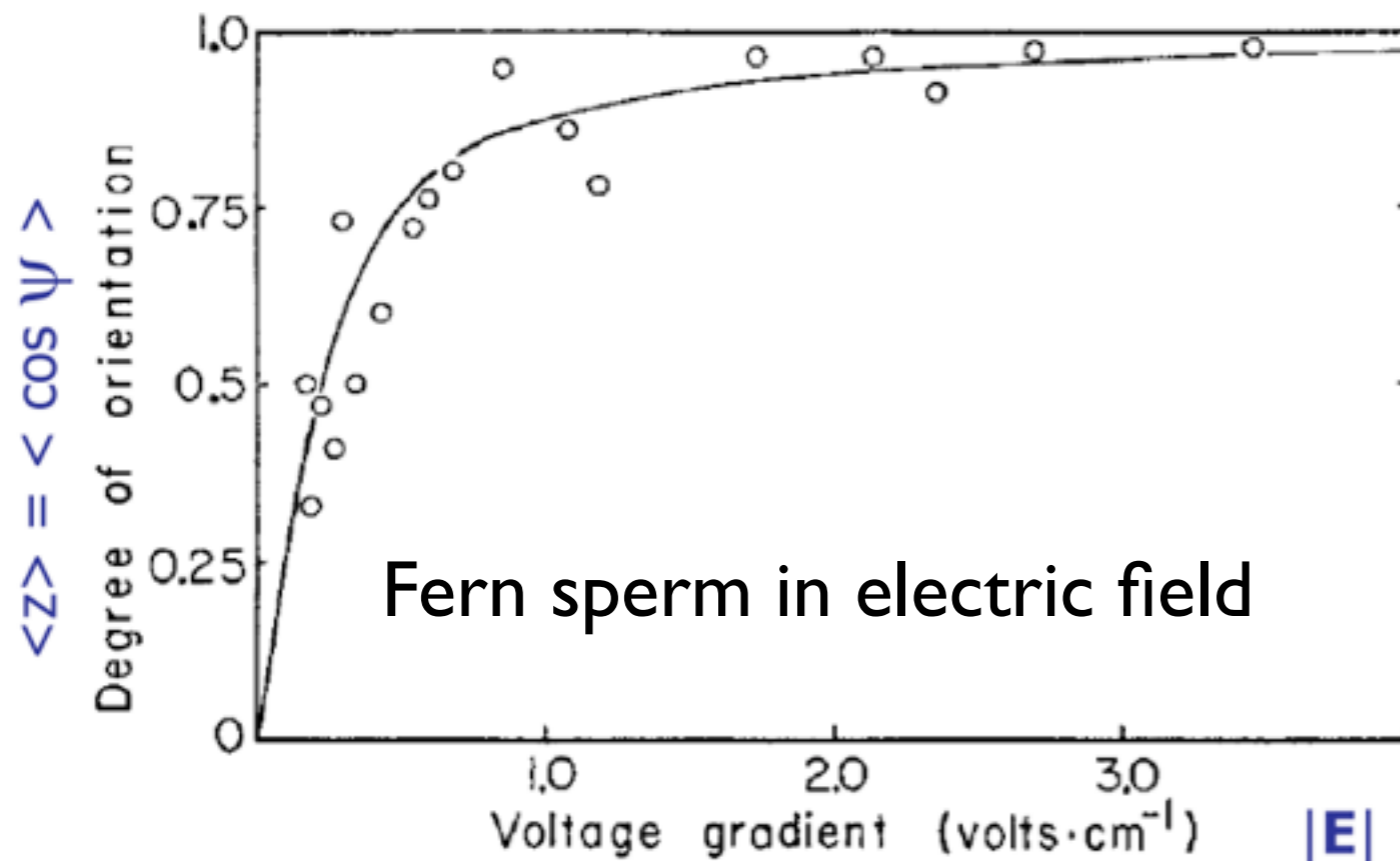
noise-induced drift

noise

Chemotaxis with noise

$$P_0(\cos \psi) \sim \exp(\cos \psi \beta / D)$$

$$\langle \cos \psi \rangle = \coth\left(\frac{\beta}{D}\right) + \frac{D}{\beta}$$



$$\beta / D \sim |E|$$

$$\beta / (D|E|) \simeq 8 \cdot 10^{-2} m/V$$

Summary Outlook

- Self-organization of motors generates chiral sperm beat

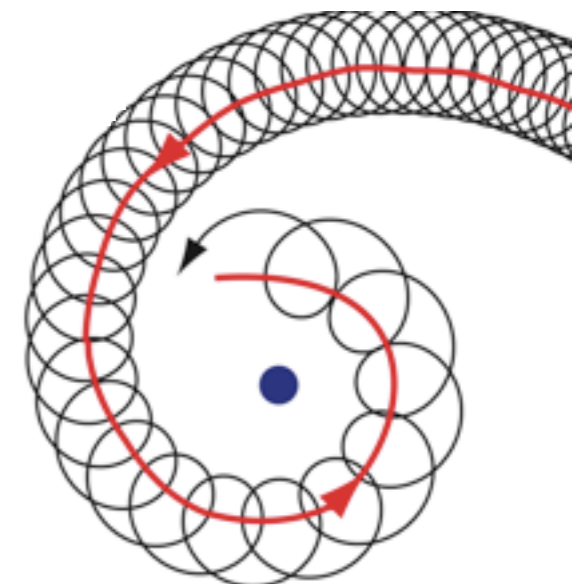
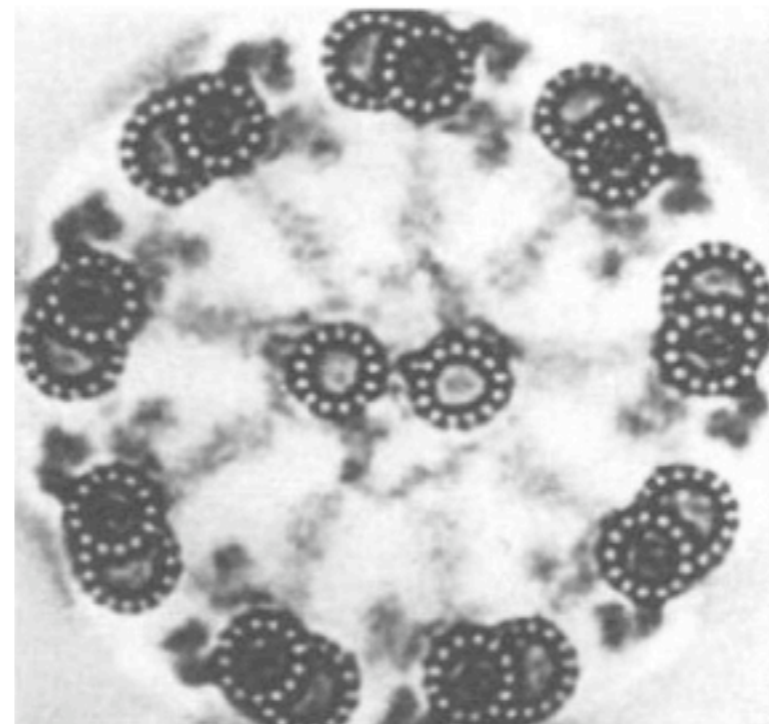
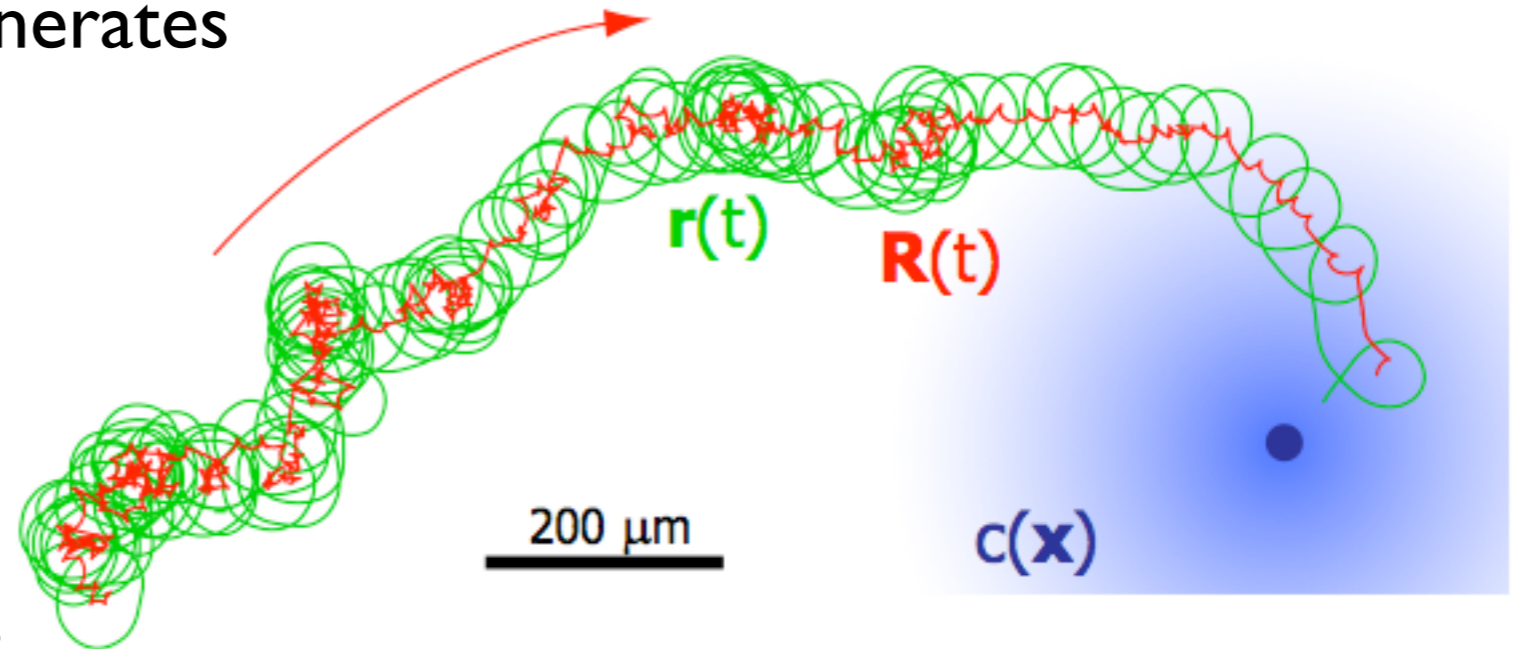
- Chiral swimming provides a mechanism for steering

- Robust under noisy conditions

- Chiral swimming:
general principle for target search

chemotaxis
phototaxis

...



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