On the Stability of Hybrid Limit Cycles and Isolated Equilibria in a Genetic Network with Binary Hysteresis

Qin Shu and Ricardo G. Sanfelice

Abstract—A mathematical model for a two-gene regulatory network is derived and several of its properties are analyzed. Due to the presence of continuous dynamics and binary hysteresis, we propose a hybrid system model. Binary hysteresis with different thresholds captures the interaction between the genes. We analyze properties of the solutions and asymptotic stability of equilibria in the system as a function of its parameters. Our analysis reveals the presence of limit cycles for a certain range of parameters, a behavior that is associated with the presence of binary hysteresis. The set of points defining the limit cycle is characterized and its asymptotic stability properties are studied. Numerical simulations are presented to illustrate some of the results.

I. INTRODUCTION

Several mathematical models have been proposed in the literature for the study of genetic regulatory networks; see [1] for a survey. In particular, boolean models are typically used to capture the dynamics of discrete switches in such networks. As introduced by Glass and Kauffman in [2], Boolean regulation functions, typically modeled as sigmoidal or step functions, can be combined with linear system models to enforce certain logic rules. The properties of such a class of piecewise linear models have been studied in the mathematical biology literature, e.g., [3], [4], [5], [6]. Snoussi presented a discrete mapping approach in [3] to study the qualitative properties of the dynamics of genetic regulatory networks. In his work, the properties of a discrete mapping were studied to determine stable isolated steady states as well as limit cycles. In [4], Gouzé and Sari employ the concept of Filippov solution to study piecewise linear models of genetic regulatory networks with discontinuities occurring on hyperplanes defined by thresholds on the variables. Chaves and coauthors [5] studied the robustness of Boolean models of gene control networks. In [6], de Jong and coauthors presented a method for qualitative simulation of genetic regulatory networks based on the piecewise linear model of [2]. Genetic regulatory networks with continuous dynamics coupled with switching can be written as a hybrid system. In [7] and [8], the authors apply hybrid systems tools to model a variety of cell biology problems.

Although it is an important phenomenon present in genetic regulatory networks, hysteresis behavior is not usually included in models of such networks. Hysteresis is characterized by behavior in which, for instance, once a gene has been inhibited due to the concentration of cellular protein reaching a particularly low value, a higher value of cellular protein concentration is required to express it. In his survey paper on the impact of genetic modeling on tumorigenesis and drug discovery [9], Huang stated that “hysteresis is a feature that a synthetic model has to capture.” Through experiments, Das and coauthors [10] demonstrated the existence of hysteresis in lymphoid cells and the interaction of continuous evolution of some cellular proteins. Hysteresis was also found to be present in mammalian genetic regulatory networks; see, e.g., [11], [12]. More importantly, hysteresis is a key mechanism contributing to oscillatory behavior in biological models [13], [14].

In this paper, we propose a hybrid system model that captures both continuous and discrete dynamics of a genetic regulatory network with binary hysteresis. We combine the methodology of piecewise linear modeling of genetic regulatory networks with the framework of hybrid dynamical systems in [15], and construct a hybrid system model for a genetic network with two genes; see Section II. Unlike piecewise linear models, our model incorporates hysteresis explicitly. We prove existence of solutions to the genetic network, a property that is typically overlooked or difficult to prove due to the discontinuity in the dynamics introduced by boolean variables. In Section III we compute the equilibria of the system in terms of its parameters. We analyze the asymptotic stability of the isolated equilibrium points and determine conditions under which a limit cycle exists. It is found that, for a particular set of parameters, hysteresis is the key mechanism leading to oscillations, as without hysteresis, the limit cycle converges to an isolated equilibrium point (cf. [3]). The stability of the limit cycle is established using a novel approach consisting of measuring the distance between solutions of hybrid systems (rather than the distance to the limit cycle as in classical continuous-time systems). In Section IV simulations validating some of our results are presented.

II. A HYBRID SYSTEMS MODEL FOR GENETIC REGULATORY NETWORKS WITH HYSTERESIS

Models of genetic regulatory networks given by piecewise-linear differential equations have been proposed in [8], [16]. Such models take the form

\[
\dot{x} = f(x) - \gamma x, \quad x \geq 0, 
\]

The notation \(x \geq 0\) is equivalent to \(x_i \geq 0\) for each \(i\).
where \( x = [x_1, x_2, \ldots, x_n]^T \) and \( x_i \) represents the concentration of the protein in the \( i \)-th cell. \( f = [f_1, f_2, \ldots, f_n]^T \) is a function, \( \gamma = [\gamma_1, \gamma_2, \ldots, \gamma_n]^T \) is a vector of constants, and \( 1 \leq i \leq n \). For each \( i, f_i \) is a function representing the rate of synthesis, while \( \gamma_i \) represents the degradation rate constant of the protein. The function \( f_i \) is typically defined as the linear combination \( f_i(x) = \sum_{\ell \in L} k_{i\ell} b_{i\ell}(x) \) where \( k_{i\ell} \) is the nonzero and nonnegative growth rate constants, \( b_{i\ell} \) is a Boolean regulation function that describes the gene regulation logic, and \( L = \{1, 2, \ldots, n\} \) is the set of indices of regulation functions.

The modeling strategy for the Boolean regulation functions \( b_{i\ell} \) is a key element that captures the behavior of a particular genetic regulatory network. A major feature of a genetic regulatory network is the presence of threshold-like relationships between the system variables, i.e., if a variable \( x_i \) is above (or below) a certain level, it could cause little or no effect on another variable \( x_j \), whereas if \( x_i \) is below (or above) this certain value, the effect on \( x_j \) would become more significant (for example, it may increase the value of \( x_j \) or inhibit the growth of the value of \( x_j \)). Boolean regulation functions can be modeled by sigmoidal or step functions, an approach that was first proposed by Glass and Kauffmann [2]. When modeling as a step function, the functions \( b_{i\ell} \) are given by the combination (linear or nonlinear) of

\[
s^+(x_i, \theta) = \begin{cases} 1 & \text{if } x_i \geq \theta \\ 0 & \text{if } x_i < \theta \end{cases}, \quad s^-(x_i, \theta) = 1 - s^+(x_i, \theta),
\]

where \( s^+(x_i, \theta) \) represents the logic for gene expression when the protein concentration exceeds a threshold \( \theta \), while \( s^-(x_i, \theta) \) represents the logic for gene inhibition.

To illustrate this modeling approach, let us consider the genetic regulatory network shown in Figure 1. Genes \( a \) and \( b \) encode proteins \( A \) and \( B \), respectively. When the concentration of protein \( A \) is below a certain threshold, it will inhibit gene \( b \). Similarly, protein \( B \) inhibits gene \( a \) when the concentration of protein \( B \) is above a certain threshold. In this way, a set of piecewise-linear differential equations representing the behavior in Figure 1 is given by

\[
\dot{x}_1 = k_1 s^-(x_2, \theta_2) - \gamma_1 x_1, \quad \dot{x}_2 = k_2 s^+(x_1, \theta_1) - \gamma_2 x_2,
\]

where \( x_1 \) is representing the concentration of protein \( A \), while \( x_2 \) is the concentration of protein \( B \). The constants \( \theta_1, \theta_2 \) are the thresholds associated with concentrations of protein \( A \) and \( B \), respectively. In this model, gene \( a \) is expressed at a rate \( k_1 \) when \( x_2 \) is below the threshold \( \theta_2 \). Similarly, gene \( b \) is expressed at a rate \( k_2 \) when \( x_1 \) is above the threshold \( \theta_1 \). Degradations of both proteins are assumed to be proportional to their own concentrations, a mechanism that is captured by \( -\gamma_1 x_1 \) and \( -\gamma_2 x_2 \), respectively.

Note that the model in (3) capturing the interaction between gene \( a \) and gene \( b \) does not incorporate binary hysteresis. Furthermore, due to the discontinuities introduced by the Boolean regulation functions, it is not straightforward to argue that solutions to (3) exist from every initial value of \( x \). In order to overcome such limitations, we propose a hybrid system with hysteresis for this two gene genetic regulatory network, to which hybrid systems tools for analysis of existence of solutions and asymptotic stability can be applied.

We model the genetic network in (3) as a hybrid system \( \mathcal{H} \) within the formalism of [17], [15], where hybrid systems are given in terms of a flow map \( F \), a flow set \( C \), a jump map \( G \), and a jump set \( D \), and solutions are parameterized by flow time \( t \) and jump time \( j \). To this end, two discrete logic variables, \( q_1 \) and \( q_2 \), are introduced. The dynamics of these variables depend on the thresholds, \( \theta_1 \) and \( \theta_2 \), respectively. As one of our goals is to introduce binary hysteresis in the model in (3), we define hysteresis level constants \( h_1 \) and \( h_2 \) associated with gene \( a \) and gene \( b \), respectively. In this way, \( q_i \) is governed by dynamics such that the evolution in Figure 2 holds.

![Fig. 1. A genetic regulatory network of two genes (a and b), each encoding for a protein (A and B). Lines ending in arrows represent genetic expression triggers, while lines ending in flatheads refer to genetic inhibition triggers.](image)

The state of the hybrid system is defined as

\[
z = [x_1, x_2, q_1, q_2]^T,
\]

where \( z \in Z := \mathbb{R}_{\geq 0}^2 \times \{0, 1\}^2 \); \( x_1, x_2 \) are (nonnegative) continuous states representing protein concentrations; and \( q_1, q_2 \) are discrete variables. Here, \( \mathbb{R}_{\geq 0} := [0, +\infty) \). We specify constants \( \theta_1 \) and \( \theta_2 \), usually inferred from biological data, satisfying \( 0 < \theta_1 < \theta_1^{\max}, 0 < \theta_2 < \theta_2^{\max} \), where \( \theta_1^{\max} \) and \( \theta_2^{\max} \) are the maximal value of the concentration of protein \( A \) and of the protein \( B \), respectively.

To define the continuous dynamics of the hybrid system capturing the evolution of (3), we rewrite the piecewise-linear differential equation (3) by replacing the \( s^+ \) term with the logic variables \( q_i \), and the \( s^- \) term with the complement of the logic variable \( q_i \), i.e., \( 1 - q_i \). Note that the discrete logic variables \( q_i \) only change at jumps, i.e., they are constants during flows. Then, \( q_i = 0 \). In this way, the continuous dynamics are governed by the differential equation

\[
\dot{x}_1 = k_1 (1 - q_2) - \gamma_1 x_1, \quad \dot{x}_2 = k_2 q_1 - \gamma_2 x_2, \quad \dot{q}_1 = q_2 = 0,
\]
and the jump set is given by

\[
\text{dom } G := \left\{ \begin{bmatrix} x_1 \\ x_2 \\ 1 - q_1 \\ q_2 \end{bmatrix} \right\}.
\] (7)

Now, we describe the discrete update of the state vector \( z \), i.e., we define \( G \) and \( D \). To illustrate this construction, we explain how to model the mechanism in Figure 2 for \( q_1 \). When

\[
qu_1 = 0 \quad \text{and} \quad x_1 = \theta_1 + h_1
\]

the state \( q_1 \) is updated to 1. We write this update law as

\[
q_1^+ = 1.
\]

When

\[
qu_1 = 1 \quad \text{and} \quad x_1 = \theta_1 - h_1,
\]

then the state \( q_1 \) is updated to 0, i.e.,

\[
q_1^+ = 0.
\]

It follows that the mechanism of \( q_1 \) in Figure 2 can be captured by triggering jumps when \( z \) belongs to

\[
\{ z : q_1 = 0, x_1 = \theta_1 + h_1 \} \cup \{ z : q_1 = 1, x_1 = \theta_1 - h_1 \}.
\]

Note that the update mechanism for \( q_2 \) is similar to that of \( q_1 \), just discussed.

We can define the flow and jump sets in a compact form by defining functions

\[
\eta_1(x_1, q_1) := (2q_1 - 1)(-x_1 + \theta_1 + (1 - 2q_1)h_1)
\]

\[
\eta_2(x_2, q_2) := (2q_2 - 1)(-x_2 + \theta_2 + (1 - 2q_2)h_2).
\]

In this way, the flow set is given by

\[
C := \{ z \in Z : \eta_1(x_1, q_1) \leq 0, \eta_2(x_2, q_2) \leq 0 \}
\] (5)

and the jump set is given by

\[
D := \{ z \in C : \eta_1(x_1, q_1) = 0 \} \cup \{ z \in C : \eta_2(x_2, q_2) = 0 \}
\] (6)

To define the jump map, first note that at jumps, the continuous states \( x_1 \) and \( x_2 \) do not change. Then, we conveniently define

\[
g_1(z) := \begin{bmatrix} x_1 \\ x_2 \\ 1 - q_1 \\ q_2 \end{bmatrix}, \quad g_2(z) := \begin{bmatrix} x_1 \\ x_2 \\ q_1 \\ 1 - q_2 \end{bmatrix},
\]

so that the jump map \( G \) is given by

\[
G(z) := \begin{cases} g_1(z) & \text{if } \eta_1(x_1, q_1) = 0, \eta_2(x_2, q_2) < 0 \\ g_2(z) & \text{if } \eta_1(x_1, q_1) < 0, \eta_2(x_2, q_2) = 0 \\ \{g_1(z), g_2(z)\} & \text{if } \eta_1(x_1, q_1) = 0, \eta_2(x_2, q_2) = 0. \end{cases}
\]

The above definitions determine a hybrid system for (3), which is given by

\[
\mathcal{H} : z \in Z \left\{ \begin{array}{c} \dot{z} = F(z) = \begin{bmatrix} k_1(1-q_2) - \gamma_1x_1 \\ k_2q_1 - \gamma_2x_2 \\ 0 \\ 0 \end{bmatrix} \\ z^+ \in G(z) \end{array} \right\} \quad z \in C
\]

\[
\in D,
\] (8)

where \( C \) is in (5), \( G \) is in (7), and \( D \) is in (6). Its parameters are given by the positive constants \( k_1, k_2, \gamma_1, \gamma_2, \theta_1, \theta_2, h_1, h_2 \), which satisfy \( \theta_1 + h_1 < \theta_1^{\max}, \theta_2 + h_2 < \theta_2^{\max}, \theta_1 - h_1 > 0, \theta_2 - h_2 > 0 \).

### III. Dynamical Properties of the Two-Gene Hybrid System Model

#### A. Existence of solutions

A solution \( z \) to \( \mathcal{H} \) is said to be nontrivial if \( \text{dom } z \) contains at least two points, complete if \( \text{dom } z \) is unbounded, Zeno if it is complete and the projection of \( \text{dom } z \) onto \( \mathbb{R}_{\geq 0}^2 \) is bounded, and maximal if there does not exist another solution \( z' \) to \( \mathcal{H} \) such that \( \text{dom } z' \) is a proper subset of \( \text{dom } z \), and \( z'(t,j) = z(t,j) \) for all \( (t,j) \in \text{dom } z \).

**Proposition 3.1:** From every point in \( C \cup D \), there exists a nontrivial solution for the hybrid system \( \mathcal{H} \) in (3). Furthermore, every maximal solution is complete and the projection of its hybrid time domain on \( \mathbb{R}_{\geq 0} \) is unbounded, i.e., every solution is not Zeno.

The proof of this result uses the conditions for the existence of solutions to \( \mathcal{H} \) in [15] for general hybrid systems.

#### B. Characterization of equilibria

We compute the set of isolated equilibrium points \( z^* \) as well as (nonisolated, dense) sets of equilibria for the hybrid system \( \mathcal{H} \) in (3). For general hybrid systems, isolated equilibrium points are points that are an isolated equilibrium point of \( \dot{z} \in F(z), z \in C \) or of \( z^+ \in G(z), z \in D \). On the other hand, an equilibrium set (not necessarily an isolated equilibrium point) for a hybrid system \( \mathcal{H} \) is defined as a set that is (strongly) forward invariant.

**Definition 3.2 (Equilibrium set):** A set \( S \subset C \cup D \) is an equilibrium set of \( \mathcal{H} \) if for every initial condition \( z(0,0) \in S \), every solution \( z \) to \( \mathcal{H} \) satisfies \( z(t,j) \in S \) for all \( (t,j) \in S \).

The following results determine the equilibria of (3) for a range of parameters of the system.

**Proposition 3.3:** The equilibria of the hybrid system \( \mathcal{H} \) in (3) is given in Table IV in terms of the positive constants \( k_1, k_2, \gamma_1, \gamma_2, \theta_1, \theta_1^{\max}, \theta_2, \theta_2^{\max}, h_1, \) and \( h_2 \) satisfying the conditions therein. The set \( S \subset C \cup D \) in case 5 is an equilibrium set and is given by

\[
S = \bigcup_{i=1}^{4} S_i,
\] (9)
where $S_t = \ln \left( \frac{\gamma_2 - \gamma_1}{\gamma_2 - \gamma_1} \right)$.

$S_1 := \left\{ x \in \mathbb{R}^2 : x = \left[ \frac{k_1}{\gamma_1} - \left( \frac{k_1}{\gamma_1} - p_0(1) \right) \exp(-\gamma_1 s) \right], s \in [0, t'_1] \times \{(0, 0)\} \right\}$

$S_2 := \left\{ x \in \mathbb{R}^2 : x = \left[ \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - p_1(1) \right) \exp(-\gamma_2 s) \right], s \in [0, t'_2] \times \{(1, 0)\} \right\}$

$S_3 := \left\{ x \in \mathbb{R}^2 : x = \left[ \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - p_2(1) \right) \exp(-\gamma_2 s) \right], s \in [0, t'_3] \times \{(1, 1)\} \right\}$

$S_4 := \left\{ x \in \mathbb{R}^2 : x = \left[ \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - p_3(1) \exp(-\gamma_2 s) \right) \exp(-\gamma_2 s) \right], s \in [0, t'_4] \times \{(0, 1)\} \right\}$

and $p_0, p_1, p_2, p_3 \in \mathbb{R}^2$ are the vertices of the set $S$, where

$t'_1 = \ln \left[ \frac{\frac{k_1}{\gamma_1} - p_0(1)}{\frac{k_1}{\gamma_1} - (\theta_1 + h_1)} \right]$, $t'_2 = \ln \left[ \frac{\frac{k_2}{\gamma_2} - p_1(2)}{\frac{k_2}{\gamma_2} - (\theta_2 + h_2)} \right]$, $t'_3 = \ln \left[ \frac{\frac{k_2}{\gamma_2} - p_2(1)}{\theta_2 - h_2} \right]$, $t'_4 = \ln \left[ \frac{\frac{k_2}{\gamma_2} - p_3(1)}{\theta_2 - h_2} \right],$

and

$p_0 = \left[ \begin{array}{c} (\theta_1 - h_1) \left( \frac{\theta_2 - h_2}{p_0(2)} \right) \\ \theta_2 - h_2 \end{array} \right]$, $p_1 = \left[ \begin{array}{c} \theta_1 - h_1 \\ (\theta_2 - h_2) \left( \frac{\frac{k_2}{\gamma_2} - (\theta_1 + h_1)}{\gamma_1} \right) \end{array} \right]$, $p_2 = \left[ \begin{array}{c} \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - (\theta_1 + h_1) \right) \left( \frac{\theta_2 - h_2}{p_1(2)} \right) \\ \theta_2 + h_2 \end{array} \right]$, $p_3 = \left[ \begin{array}{c} \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - (\theta_2 + h_2) \right) \left( \frac{\theta_1 - h_1}{p_2(1)} \right) \\ \theta_2 + h_2 \end{array} \right]$, $p_4 = \left[ \begin{array}{c} \frac{k_2}{\gamma_2} - \left( \frac{k_2}{\gamma_2} - (\theta_2 + h_2) \right) \left( \frac{\theta_1 - h_1}{p_2(1)} \right) \\ \theta_2 + h_2 \end{array} \right]$

Moreover, the period of the limit cycle is given by

$T = t'_1 + t'_2 + t'_3 + t'_4$.

$\gamma_i$ is the $i$-th component of $\gamma$, $\gamma_2$ and $\gamma_3$ are the vertices of the set $S$.

C. Stability analysis

For convenience in the following analysis, we rewrite the flow set $C$ as $C = \bigcup_{i=1}^4 C_i$, where

$C_1 := \{ z \in \mathbb{R}^2 : q_1 = 0, q_2 = 0, x_1 \leq \theta_1 + h_1, \theta_2 \leq \theta_2 + h_2 \}$,

$C_2 := \{ z \in \mathbb{R}^2 : q_1 = 1, q_2 = 0, x_1 \geq \theta_1 - h_1, \theta_2 \leq \theta_2 + h_2 \}$,

$C_3 := \{ z \in \mathbb{R}^2 : q_1 = 1, q_2 = 1, x_1 \geq \theta_1 - h_1, \theta_2 \geq \theta_2 - h_2 \}$,

$C_4 := \{ z \in \mathbb{R}^2 : q_1 = 0, q_2 = 1, x_1 \leq \theta_1 + h_1, \theta_2 \geq \theta_2 - h_2 \}$.

1) Asymptotic stability of isolated equilibrium points: The following propositions determine the stability properties of the isolated equilibrium points in Table I.

Proposition 3.4: For case 1, 2, and 4 in Table I, the corresponding equilibrium points to $H$ in $\mathbb{R}^3$ are globally asymptotically stable.

Proposition 3.5: For case 3 in Table I if $z(0, 0) \in C_2$, then we have that $\lim_{t \to \infty} z(t, j) = z^*_1$; if $z(0, 0) \in C_1$ or $z(0, 0) \in C_4$, then $\lim_{t \to \infty} z(t, j) = z^*_2$. If $z(0, 0) \in C_3$, then $\lim_{t \to \infty} z(t, j) = z^*_1$ or $z^*_2$. Furthermore, $z^*_1$ and $z^*_2$ are stable.

2) Stability properties of the limit cycle: Now, we determine conditions on the parameters under which the limit cycle $S$ defined in (9) is asymptotically stable. As shown in Figure 5(c), the natural metric (shown in dashed line) defined by the distance between the trajectories $z$ of $H$ and the set $S$ is not necessarily decreasing, even though Figure 5(a) shows that the trajectory converges to $S$. In fact, as depicted in the figures, the trajectory $x$ approaches $S$ for some time and then gets far away from it (around the corners), until a jump to a new value of $q$ occurs.

To overcome this issue, we augment the hybrid system $H$ with a state $\zeta \in \mathbb{R}^2$ and with continuous dynamics governed by a flow map given by a copy of the one for $x$, that is,

$\dot{\zeta} = \left[ \begin{array}{c} k_1 (1 - q_2) - \gamma_1 \zeta_1 \\ k_2 q_1 - \gamma_2 \zeta_2 \end{array} \right]$. 

<table>
<thead>
<tr>
<th>Conditions on constants</th>
<th>Equilibria</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 ( \theta_1 + h_1 &lt; \frac{k_1}{\gamma_1} &lt; \frac{\theta_1 + h_1}{\gamma_1} ) ( \theta_2 + h_2 )</td>
<td>$z^*_1 := \left[ \begin{array}{c} k_1 \ k_2 \ 1 \ 0 \end{array} \right]^T$</td>
</tr>
<tr>
<td>2 ( 0 &lt; \frac{k_1}{\gamma_1} &lt; \theta_1 - h_1 )</td>
<td>$z^*_2 := \left[ \begin{array}{c} k_1 \ 0 \ 0 \ 0 \end{array} \right]$</td>
</tr>
<tr>
<td>3 ( \theta_1 - h_1 &lt; \frac{k_1}{\gamma_1} &lt; \theta_1 + h_1 ) ( \theta_2 + h_2 ) ( \frac{\theta_1 + h_1}{\gamma_1} )</td>
<td>$z^<em>_1$ or $z^</em>_2$</td>
</tr>
<tr>
<td>4 ( \theta_1 - h_1 &lt; \frac{k_1}{\gamma_1} &lt; \theta_1 + h_1 ) ( \theta_2 + h_2 ) ( \frac{\theta_1 + h_1}{\gamma_1} )</td>
<td>$z^*_2$</td>
</tr>
<tr>
<td>5 ( \theta_1 + h_1 &lt; \frac{k_1}{\gamma_1} &lt; \frac{\theta_1 + h_1}{\gamma_1} ) ( \theta_2 + h_2 ) ( \frac{\theta_1 + h_1}{\gamma_1} )</td>
<td>equilibrium set $S$ defined in (9)</td>
</tr>
</tbody>
</table>
The discrete dynamics of $\zeta$ are chosen so that jumps occur when jumps of $\mathcal{H}$ occur and, at such jumps, $\zeta$ is updated via the difference inclusion

$$
\zeta^+ \in \tilde{G}(x, q, \zeta).
$$

To define the jump map $\tilde{G}$, we consider the case $\gamma_1 = \gamma_2$ and we extend to $\mathbb{R}^2$ the set of points $S_i$, $i \in \{1, 2, 3, 4\}$, that is, we define the (unbounded) set

$$
\tilde{S} = \bigcup_{i=1}^{4} \tilde{S}_i,
$$

where

$$
\begin{align*}
\tilde{S}_1 &= \{ x \in \mathbb{R}^2 : x_2 = m_1 x_1 - m_1 p_1(1) + p_1(2) \} \times \{(0, 0)\}, \\
\tilde{S}_2 &= \{ x \in \mathbb{R}^2 : x_2 = m_2 x_1 - m_2 p_1(1) + p_1(2) \} \times \{(1, 0)\}, \\
\tilde{S}_3 &= \{ x \in \mathbb{R}^2 : x_2 = m_3 x_1 - m_3 p_1(1) + p_1(2) \} \times \{(1, 1)\}, \\
\tilde{S}_4 &= \{ x \in \mathbb{R}^2 : x_2 = m_4 x_1 - m_4 p_1(1) + p_1(2) \} \times \{(0, 1)\}.
\end{align*}
$$

The constants $m_i$ are defined as

$$
\begin{align*}
m_1 &= \frac{p_0(2) - p_1(2)}{p_0(1) - p_1(1)}, & m_2 &= \frac{p_2(2) - p_1(2)}{p_0(1) - p_1(1)}, \\
m_3 &= \frac{p_2(2) - p_3(2)}{p_2(1) - p_3(1)}, & m_4 &= \frac{p_0(1) - p_3(1)}{p_2(1) - p_3(1)}.
\end{align*}
$$

During flows, the set $\tilde{S}$ is forward invariant for the state component $\zeta$ (both during flows and jumps) along the dynamics of $q$ governed by $\mathcal{H}$. This is the reason we restrict $\zeta$ to belong to $\tilde{S}$ for the current value of $q$. Then, due to the stability properties of the error system with state $\zeta - x$, the distance between $x$ and $\zeta$ strictly decreases during flows. With this useful property of the trajectories while flowing, at jumps due to the distance between $x$ and $\zeta$ governs the stability properties of the error system with state $\zeta - x$, the distance between $x$ and $\zeta$ strictly decreases during flows.

![Trajectories $x$ and $\zeta$ on the plane.](image1)

![Distance between trajectory $x$ and $\zeta$ (solid), and distance between $x$ and $S$ (dashed).](image2)

**Theorem 3.6:** For positive constants $k_1, k_2, \gamma_1, \gamma_2, \theta_1, \theta_1^{\text{max}}, \theta_2, \theta_2^{\text{max}}, h_1, \text{and } h_2$ such that

$$
\begin{align*}
\gamma_1 &= \gamma_2, \\
|m_1| &\leq \min\{|m_2|, |m_4|\}, \\
|m_3| &\leq \min\{|m_2|, |m_4|\},
\end{align*}
$$

where, for each $i \in \{1, 2, 3, 4\}$, $m_i$ are given in (11), the following holds:

1. The set $\tilde{S}$ is globally asymptotically stable for $\mathcal{H}$. In particular, each maximal solution to $\mathcal{H}$ satisfies

$$
d((x(t, j), q(t, j)), \tilde{S}) \leq \exp(-\gamma t) d((x(0, 0), q(0, 0)), \tilde{S})
$$

for all $(t, j) \in \text{dom}(x, q)$, where $d((x, q), \tilde{S}) = \min_{(\zeta, q) \in \tilde{S}} |x - \zeta|$.  
2. The set $\tilde{S}$ in case 5 of Table 1 is globally attractive for $\mathcal{H}$, i.e., every solution to $\mathcal{H}$ converges to $S$.

Figure 3 shows trajectories $x$ and $\zeta$ as well as the distance between them obtained from the hybrid system augmented with the state $\zeta$. As Figure 3(b) indicates, this distance (solid) decreases to zero while, as pointed out earlier, the natural distance between $x$ and $S$ (dashed) does not.

Due to the regularity properties of the data of $\mathcal{H}$, the asymptotic stability guaranteed by Theorem 3.6 is robust to small perturbations.

**IV. NUMERICAL RESULTS**

We illustrate numerically the more interesting case when the parameters lead to a limit cycle.

When the parameters are in the region $\theta_1 + h_1 < \frac{k_1}{\gamma_1} < \theta_1^{\text{max}}$, $\theta_2 + h_2 < \frac{k_2}{\gamma_2} < \theta_2^{\text{max}}$, the set of points $S$ in (9) defines the equilibria. First, we compute this set of points for $k_1 = k_2 = 1$, $\gamma_1 = \gamma_2 = 1$, $\theta_1 = 0.6$, $\theta_2 = 0.5$, $h_1 = h_2 = 0.01$. Figure 4(a) shows the set of points $S$ projected to $\mathbb{R}^2$ for these parameters. For the same parameter values, the period of the limit cycle obtained from Proposition 3.3 is $T = 0.8230$ sec, where $t'_1 = 0.2552$ sec, $t'_2 = 0.2359$ sec, $t'_3 = 0.1594$ sec, $t'_4 = 0.1724$ sec. Figure 4(b) confirms this result.
when the magnitude of hysteresis tends to zero, the size of the limit cycle depends on the value of hysteresis $h_2$. Each solution converges to the limit cycle $S$. The size of the limit cycle is reduced as $h_1, h_2$ gets smaller. From our results we know that the size of the limit cycle depends on the value of hysteresis parameters. When the magnitude of hysteresis tends to zero, the set $S$ approaches a point, which is given by $(\theta_1, \theta_2)$ (see similar case shown in Figure 5(d)).

Finally, Figure 6 shows the case when $\gamma_1 \neq \gamma_2$. In this case, the trajectories approach the limit cycle given in (9).

\section{V. Conclusion}

In this paper, a mathematical model of a genetic regulatory network has been developed under the formalism of hybrid dynamical systems. The model presented in this paper permits a quantitative analysis of the cellular protein dynamics under the influence of protein concentration thresholds and initial conditions. The analysis of the hybrid model with two genes determines conditions guaranteeing the existence of solutions, the equilibria of the system, and the stability properties of the equilibria (and its robustness). In particular, we have revealed conditions on the parameters that, when hysteresis is present, the interaction between the concentrations of two proteins leads to oscillatory behavior. Such a behavior is impossible in a two-gene network without hysteresis.

\begin{thebibliography}{10}


\end{thebibliography}