# Neural Dynamics Part I

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#### recall: Braitenberg vehicles...



### behavioral dynamics



# Selection

bistable dynamics for bimodal intensity distribution => bistable (nonlinear) dynamics makes selection decision



... with more complex nervous system





# ... keep selection decision "in mind"?



### ... keep selection decision "in mind"?

- when sensory information is removed => keep decision in working memory
- for this need an "inner state" of the nervous system that "stores" that decision => neural activation



#### Activation

#### neural state variable activation

- Inked to membrane potential of neurons in some accounts
- Inked to spiking rate in our account
- through: population activation... (later)

### Activation

- activation as a real number, abstracting from biophysical details
  - Iow levels of activation: not transmitted to other systems (e.g., to motor systems)
  - high levels of activation: transmitted to other systems
  - as described by sigmoidal threshold function
  - zero activation defined as threshold of that function



#### Activation

#### compare to connectionist notion of activation:

same idea, but tied to individual neurons

#### compare to abstract activation of production systems (ACT-R, SOAR)

quite different... really a function that measures how far a module is from emitting its output...

#### activation evolves in continuous time

no evidence for a discretization of time, for spike timing to matter for behavior

activation variables u(t) as time continuous functions...

$$\tau \dot{u}(t) = f(u)$$

what function f?







In a dynamical system, the present predicts the future: given the initial level of activation u(0), the activation at time t: u(t) is uniquely determined



- stationary state=fixed point= constant solution
- stable fixed point: nearby solutions converge to the fixed point=attractor



exponential relaxation to fixed-point attractors

=> time scale



attractor structures ensemble of solutions=flow



![](_page_18_Figure_1.jpeg)

$$\tau \dot{u}(t) = -u(t) + h + \text{ inputs}(t)$$