Sensory dependencies rapidly and autonomously yield generalizable representations in recurrent cortical-like networks

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Abstract

How biological brains can learn so quickly to become operational and achieve complex behavior remains an unresolved issue. Here we introduce a 'neuromorphic' learning strategy that resembles how immature biological brains learn by consisting of continual random activations of a complex mechanically coupled system with rich, dynamic intrinsic sensor dependencies, in this regard reminiscent of a biological body. Using a dynamic model of biological skin tissue with embedded sensors, we trained small, recurrent networks that emulated a primordial cortex and featured excitatory and inhibitory neurons with simultaneous independent learning in both types of synapses. Training with non-repetitive, random activations of the skin, where the recurrent network activity state was inherited between activations, autonomously led to rapid acquisition of remarkably generalizable representations of a predictive nature. The network could separate inputs and solve a kinematics task that had never been encountered, also after substantial parts of the sensor population were deleted. This strategy of focussing learning on the dominant regularities in dynamic sensory information can potentially explain complex brain operation and efficient learning.

Introduction

A striking difference between biology and artificial intelligence network technology is that biological neuronal networks seem to be learning from much fewer examples and much less repetitious inputs (1). We hypothesized that one reason could be that the brain learns about the world through the biomechanical constraints provided by its body. The body is composed of tissues with dynamic compliances, such as in the skin (2) but also in deep tissues in general, which essentially make the whole body mechanically coupled (3). Because the biological sensors are embedded within such tissues, they can display complex patterns of dynamic dependencies, translating to spatiotemporal regularities in their population level activity (2). Such regularities could be used to represent in principle any conceivable complex, distributed stimulus by means of the principle of superposition (2, 4, 5, 6). A learning strategy that focuses on such regularities, through varied rather than repetitious behavior, could therefore rapidly result in more efficient and generalizable network representations, and could be more robust to sensor loss or sensor drift.

We tested the general principles of this postulate by studying learning from sensor inputs generated by a recent model of skin tissue dynamics (2) in a recurrent neuronal network, which was made as small and generic as possible while still being a relevant comparison to simplified subnetworks of primordial cortex (7, 8). The two-layered network was composed of excitatory and inhibitory neurons (Fig. 1A) where each excitatory and inhibitory synapse was independently and continuously subject to Hebbian-like plasticity. We used a non-spiking neuron model (8), which emulates the impact of the neuronal dynamics of membrane time constants and conductance-based synaptic

integration in biological neurons. The skin sensory inputs were provided to the first layer, to both excitatory and inhibitory neurons, although without a thalamus. The ubiquitous recurrency of our network was motivated by that recurrent excitatory loops are a common feature in neocortical circuits (9, 10, 11, 12) and recurrent synapses between pyramidal neurons can be considered to constitute the majority of neocortical synapses (13, 14) in principle supporting all-to-all connectivity locally (14, 15). Inhibitory interneurons can provide lateral inhibition (16, 17, 18, 6) and feed-forward inhibition (19, 20). But they also make synapses on other inhibitory neurons, thereby potentially forming recurrent disinhibitory loops as well (21, 22, 23, 24) and are believed to participate in forming all-to-all local cortical networks (15) in addition to providing long range intracortical connections (25, 26, 27) and receiving both local and long range intracortical connections as well as thalamic sensory inputs (19, 28).

Results

Network learning from intrinsic dependencies

Figure 1B illustrates the mass-spring-damper implementation of the dynamic skin model (2) used to model skin tissue dynamics. Although the skin model could provide 1000's of sensor signals we used only 10 of those sensors, which corresponded to the force signals generated in the 10 springs connected to the central mass (indicated in black in Figure 1B). Figure 1C shows one example of a skin input (top panel). The temporal profiles of the sensor responses illustrate that they provided non-redundant information. When the other four types of skin inputs were also considered, the relative uniqueness of the signal of each individual sensor was even clearer (Fig. S1).

As the actions driving early learning in biological brains are far from structured ('*motor babbling*'; see (29, 30, 31)), our network learning consisted of a series of random, non-repetitive activations of the skin model (1160 stimulus presentations), in what would correspond to about one hour of random haptic interaction in a biological system. The continual nature of the activations also meant that the circulating activity within the recurrent network was never allowed to fully relax between consecutive stimuli. Hence, each stimulus presentation was met with a unique processing state in the network, rendering each learning phase even more unique. To test the impact of the intrinsic dependencies across the sensor population, we compared the results of the network learning from the skin inputs ('skin network') with the same network learning from pre-generated random patterns of Gaussian signals ('Gaussian network') (Fig 1C), which had similar dynamic properties as the skin inputs (Fig S2). Figure 1D-G illustrates the neuron activities overall as well as in detailed snapshots pre- and post-learning, for the 'skin network' as well as for the 'Gaussian network'. The neuron signals became more diversified in the skin network compared to the Gaussian network (Fig. 1F,G), i.e. there was a richer set of covariance patterns across the neuron population.

Separation of naive inputs

Our critical research question was if the skin network could separate inputs that it had not previously experienced. To address this question, we analyzed the activity distribution patterns across the neuron population using principal component analysis (PCA). Post-learning skin networks and Gaussian networks (Fig. 2A) were provided skin inputs they had not experienced (Fig. 2B). They differed either with respect to the spatial force input patterns (Fig. S1) or the temporal profiles/kinematics of non-patterned force impulses (Fig. S3). We also tested the impact of removing sensors (Fig. 2B) post-learning. For the five naive skin inputs, the skin networks provided more distinctly different

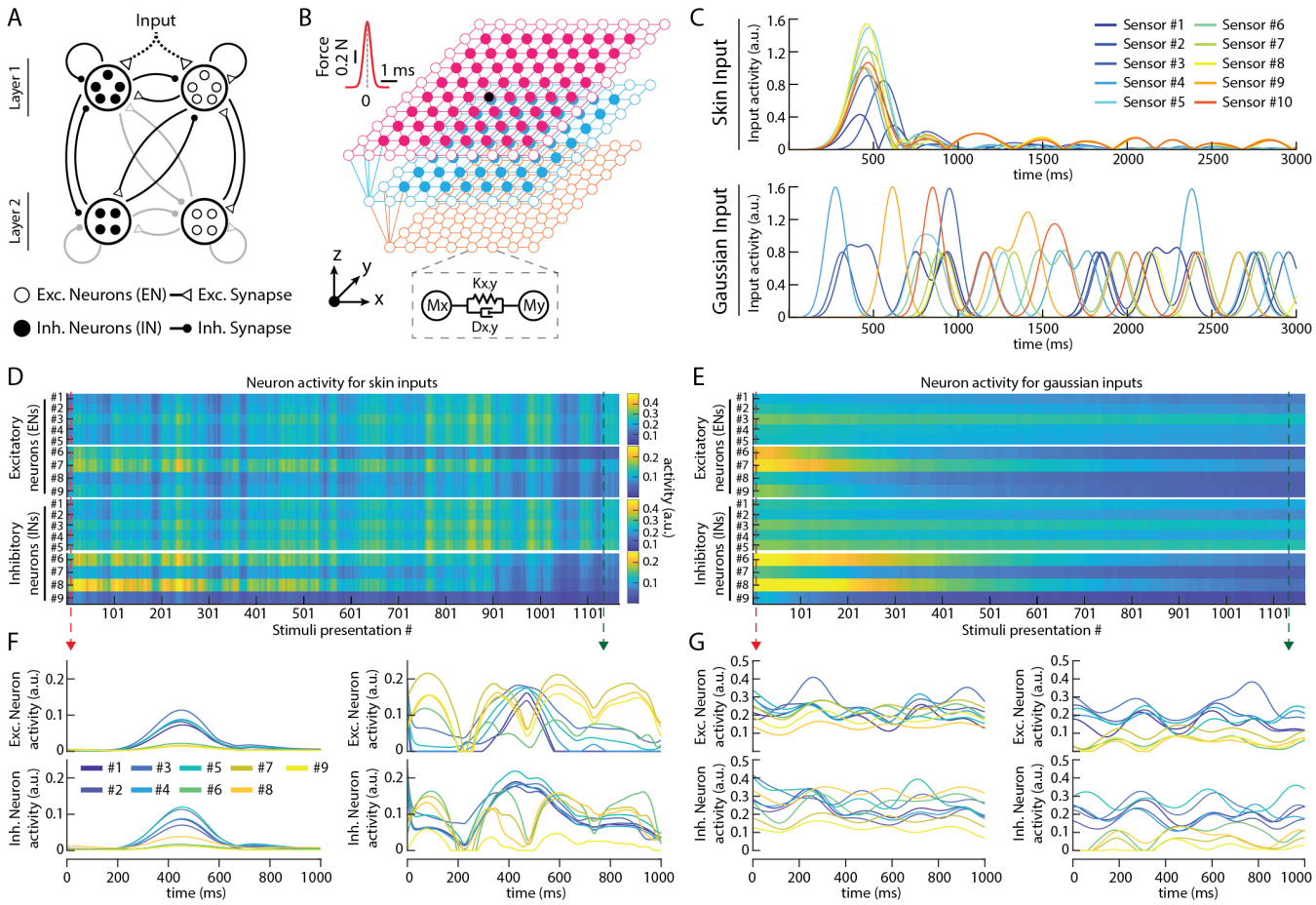

Figure 1: **Learning from sensors embedded in a dynamic skin tissue model** (**A**) Schematic of the fully connected network structure. (**B**) Three-layer damped mass-spring skin model (2) used to generate the intrinsically dependent sensory inputs. Top left corner, time profile of the applied forces for the different inputs. Masses, shown as nodes, were connected by springs and dampers represented as links (internode distance 1.0 mm). Note that the actual model was larger and comprised 1085 nodes in total. Nodes shown as circles along the edges were fixed nodes, including the entire third layer. The activity from the 10 sensors connecting to the mass at the center of the superficial layer (black node) were provided as input to the network. (**C**) Example sensory input used for network learning. *Top:* Skin model sensor inputs; *Bottom* Gaussian sensor inputs. (**D**) Individual neuron activities (moving average across 50 input presentations) during learning from an uninterrupted sequence of 1160 random skin inputs. This network had initial connectivity%=23. (**E**) Corresponding network learning from the Gaussian inputs. (**F**) Activities of the excitatory (top) and inhibitory (bottom) neurons to an example skin input at the beginning (left) and at the end (right) of the learning. (**G**) Similar display for a Gaussian input.

neuron population activity trajectories in the PC space (Fig. 2C); Fig. S4 illustrates the PC trajectories for the untrained initial random network), and also provided better classification accuracy across the different neuronal noise levels (Fig. 2D). Notably, when removing 20% of the sensors, the PC trajectories did not substantially alter (Fig. S5) and the classification was unchanged or improved for the skin network, in contrast to the Gaussian network (Fig. 2D, bottom panel). For the separation of force impulses with different kinematics, a type of task that the networks had not learnt, there was an even clearer separation between the two network types (Fig. 2E,F), even more so with sensor loss (Fig. 2F, bottom panel). Across all tests, the skin network also outperformed the untrained network, except at the lowest noise levels where the networks approached deterministic behavior. This is in line with that Reservoir Computing networks can have intrinsic dynamic modes without any training of the recursive synapses, which can provide some level of separation capacity of the dynamic modes of an input (32).

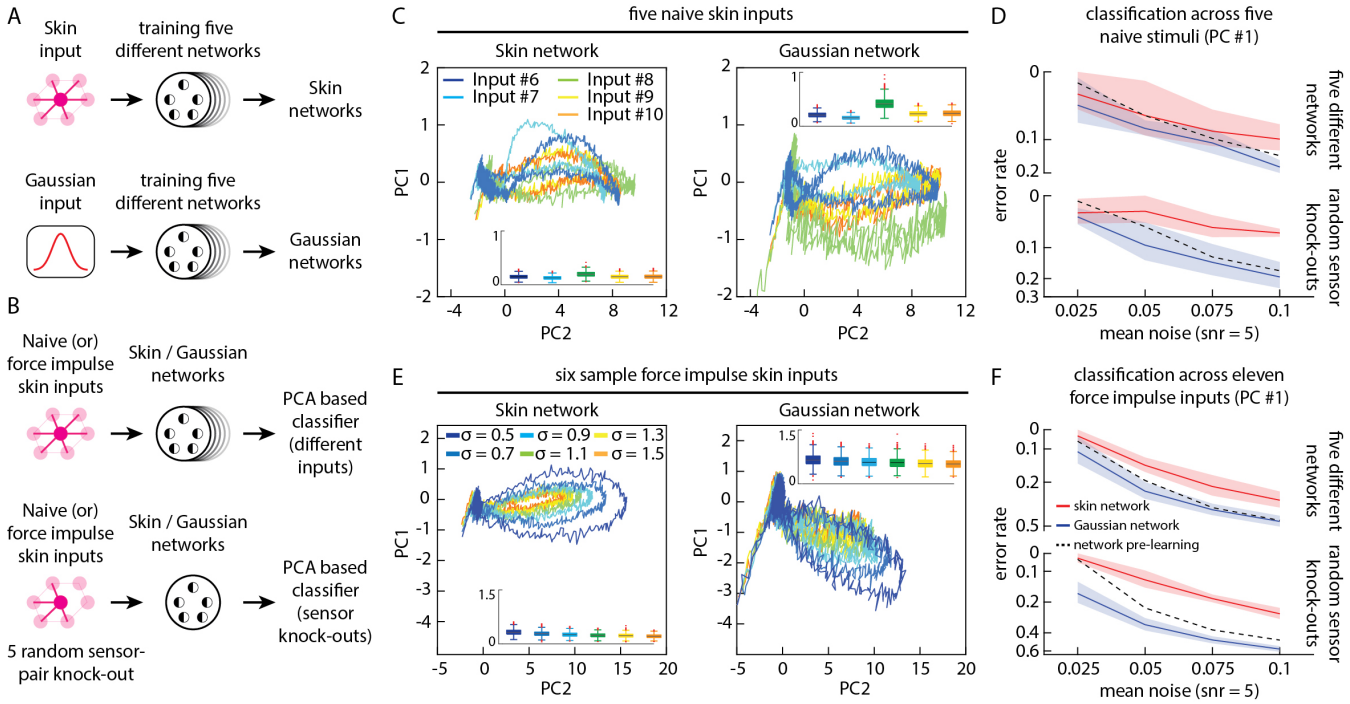

Figure 2: **Generalization to naive inputs and robustness to sensor loss in skin networks** (**A**) The network learned from skin inputs or from Gaussian inputs. (**B**) Protocols used for comparing the classification generalization and robustness. (**C**) The responses of the excitatory neuron population for the five naive skin inputs Fig. S1 F-J; color coded) projected on the first two principal components (PCs), comparing the skin and Gaussian networks. *Inset*: the variances of the PC scores for the five different inputs. Same network as in Fig. 1. (**D**) Classification accuracies (mean and variance) across the five naive skin inputs at different noise levels. (**bottom**) Classification accuracies across the same five naive skin inputs with random sensory knock-out. (**E**) Similar display as in **C**, but for eleven force impulse skin inputs (Fig. S3). (**F**) Classification accuracy across these eleven force impulse skin inputs.

Synaptic weight changes

Relative to the untrained network (Fig. 3A-C), skin inputs caused an increase in the weights of the sensory synapses, whereas the opposite effect applied to the Gaussian network (Fig. 3D; note the scale difference for the two networks). There were also extensive reorganization and excitatory/inhibitory re-balancing of the internal network synapses (Fig. 3E, Fig. S6, S7), which can explain how the skin network activity could decrease (Fig. 1D,E) as its synaptic weights increased. We repeated the same learning for 30 different network settings, each fully connected, identified by their 'Initial connectivity%'. This label was reflective of the mean weights of the synapses but also an index indicating the weight distribution (see Fig. S8, S9) and skewness (Fig. S10), in order to test our learning mechanisms for a range of initial networks configurations. The magnitude of the initial network activities scale linearly with the 'Initial connectivity%'s (Fig. S11). As illustrated in Fig. 3F-I, the synaptic weight changes to both excitatory and inhibitory neurons were approximately congruent across the different Initial connectivity%'s for both network types. Whereas the sensory synapses changed the most, the internal network synapses could change almost as much for the networks with the intermediate Initial connectivity%, in particular the feedback connections from layer 2 to layer 1 (Fig. S12). We also tested if the initial weight skewness could explain these weight changes more clearly, but found no apparent relationship (Fig. S13). The Gaussian networks overall had lower mean weight changes. Notably, the skin networks with the highest Initial connectivity (%) did not display much weight changes (Fig. 3F-I) and as we found out next this impacted the input separation of the network.

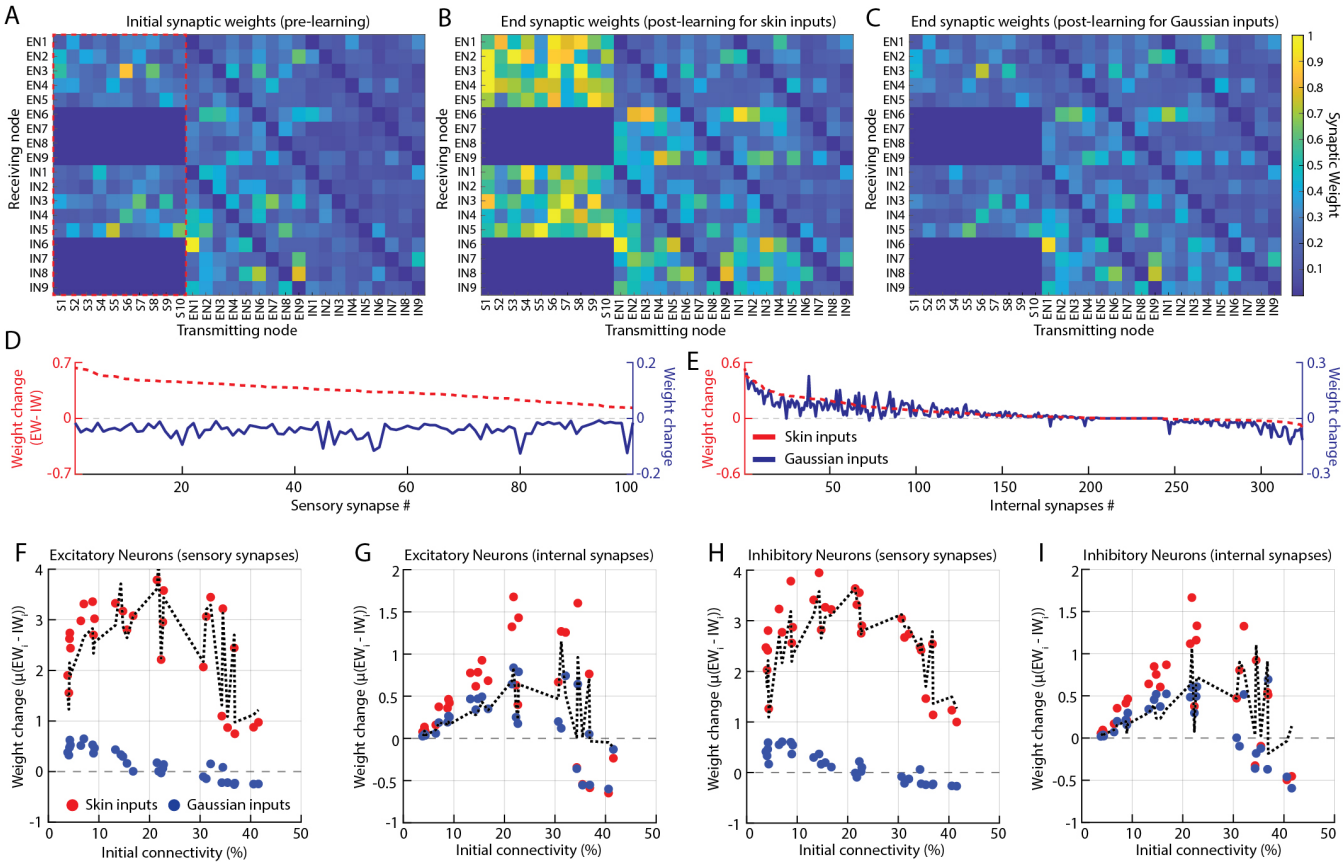

Figure 3: **Synaptic weight changes following learning** (**A**) Initial synaptic weights for an example network with the sensory synapses within the red dotted box. (**B**) The synaptic weights post-learning (end Weights) in the skin network. (**C**) The synaptic weights post-learning in the Gaussian network. (**D**) Sensory synapses sorted by their magnitude of weight change after learning from the skin input, for comparison of the skin network and the corresponding Gaussian network. (**E**) Similar display as in **D**, but for weight changes across non-sensory synapses (internal synapses). (**F-I**) Average net weight changes post-learning, sorted by type of synapse, across networks with varied initial weight configuration (Fig. S8, S9). The dashed lines indicate the difference in average net weight changes between the corresponding skin networks and the Gaussian networks.

Differentiation of neuron activity patterns

The input separation in Fig. 2 depended on the time series of activity distribution patterns across the neuron population. Such activity distribution patterns are salient in the cortex (33). Differentiation of the activity distributions between the neurons across different inputs, indicative of a complementarity of the neuronal encoding, can be viewed as a proxy for the input separation capability of the network (5, 34). Indeed, cortical neuron populations display a great degree of differentiation in their activity patterns across various conditions (34, 35, 36, 37, 38). In variational autoencoder networks, a type of artificial neural network, enforcing such differentiations between the neural nodes during the learning of a dynamics tasks also leads to more efficient representations (39). In our networks, such complementariness should naturally arise as the learning mechanisms of the inhibitory synapses would make them 'chase' the excitatory paths that arise as excitatory weights increase. Incomplete inhibition of the inputs that the excitatory neurons try to propagate will in turn lead to decorrelation between the neurons (Fig.5).

The cross-correlation used to quantify the complementarity of neuronal encoding did indeed decrease substantially with learning in the skin networks (Fig. 4A,B). However, for the networks with the highest connectivity% such a drop did not occur. These networks also had the lowest degree of restructuring of their synaptic weights (Fig. 3F-I)

and it appeared that the intrinsic dynamics in these tight networks were too strong to become impacted by the sensory synaptic activities. We investigated if a drop in cross-correlation in these cases could be 'rescued' by a tweak to the Hebbian learning rule, which relies on activity correlation between the synapse and the postsynaptic signal. In this tweak, the excitatory synapses were only allowed to 'see' a high pass filtered version of the postsynaptic signal for its learning (See Methods for the biological rationale). Indeed, this 'Excitatory synapse learning signal filter' led to drops in the cross-correlations for networks with high initial connectivity%, with almost no impact on networks with the lowest initial connectivity% (Fig. 4C, Fig. S15. Also the overall pattern of synaptic weight changes remained unchanged (comparing Fig. S16 with Fig. 3F-I). Importantly, for the networks with high initial connectivity%, the learning signal filter also led to a 'rescue' of their separation capability (Fig. 4D). Hence, also tightly connected recursive networks could learn to separate dynamic sensory inputs using Hebbian-like learning. When removing specific connection types we found that inhibitory synapses, both laterally within the layers and feed-forward, led to significantly higher cross-correlations (Fig. S17) and thereby less separation capacity.

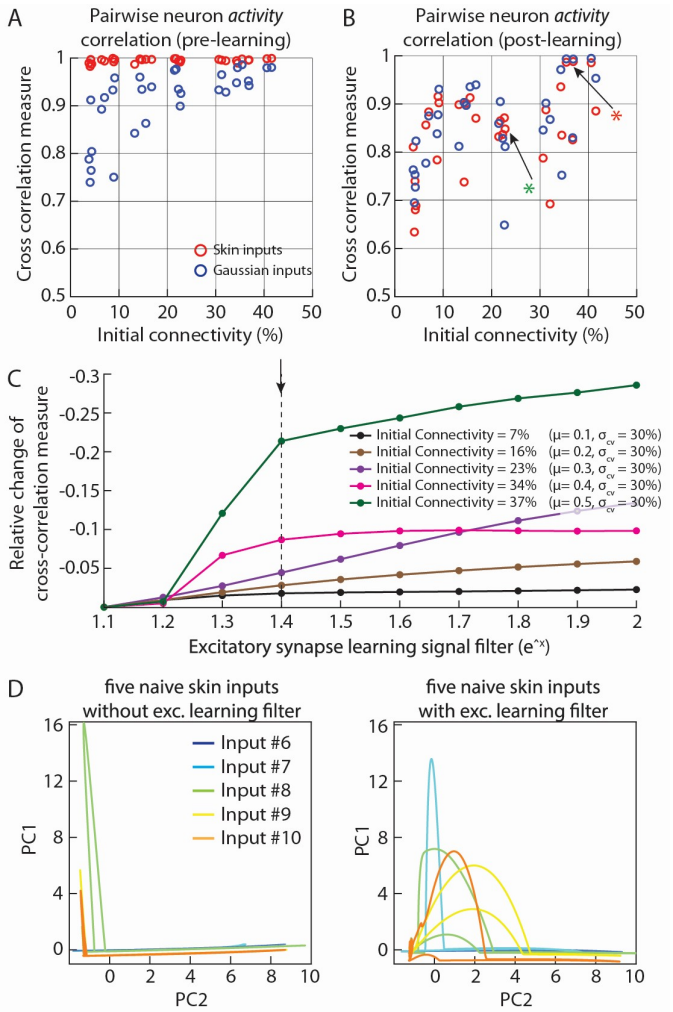

Figure 4: **Diversification of the neuronal activity following learning *and* effect of the excitatory learning signal filter.**(**A**) Average pairwise cross-correlations across all the ENs pre-learning. (**B**) Same observation post-learning. Arrows indicate the succesful network illustrated in Figs **??** and the network that failed to learn without learning signal filter (red asterisk). (**C**) Relative changes in the cross correlation measure in skin networks across different learning signal filter exponents. Dashed line indicates the exponent (1.4) used in the test in (D). (**D**) PC trajectories of the failing network without the learning signal filter (left). (right) same network after learning using the learning signal filter.

Discussion

The main point of the present paper was to illustrate the impact of a learning strategy that depended on inputs from sensors distributed across a system with rich internal mechanical couplings and dynamics, similar to biological tissue, in a recurrent, cortex-style neuronal network. Learning was achieved using diverse tissue activations, similar to how it occurs during early biological development, which is characterized by mostly disorganized, semi-chaotic movements (40, 29, 41). As the recursive network activity had a dynamic time-continuous internal activity, similar to the real cortex *in vivo* (38, 42, 43, 44), each sensor activation was combined with a unique network state. The learning occurred independently at each individual excitatory and inhibitory synapse, and hence the identification of the regularities in the sensory inputs were fully autonomous by the network. We found this 'neuromorphic' learning strategy to quickly converge to highly generalizable network representations, applicable to separate inputs that differed in their spatial and/or kinematic character compared to those experienced during network learning.

With the neuromorphic learning strategy we argue that the most important aspects of the sensory information for the brain would be which dependency states that apply at the moment (5), i.e. the regularities or invariants in the spatiotemporal patterns of the sensor population activity. In this representation strategy, the details of individual sensor activation patterns become less relevant, which we showed with the conserved separation capacity when 20% of sensors were removed post-learning (Fig. 2). Since the regularities across the sensors derive from the mechanical couplings in the tissue, they will reappear across in principle any stimulus/activation context and can thus be used by the network to separate stimuli that are dissimilar from those previously experienced. The aspects of the sensor population regularities that correlate the best with the intrinsic network dynamics will also be those that are the most easily learnt by the recurrent network, which in turn will gradually become better at mirroring the dominant tissue dynamics (i.e. regularities). This was indicated by that the learning created attractor-like temporal trajectories in the activity distributions across the neuron population (Fig. 2). Interestingly, when the network begins to mirror the dominant dynamics in the mechanical system, this is equivalent to that the network begins to predict its properties. Our network architecture and learning mechanisms therefore feature specific low-level network mechanisms that can achieve predictive coding, which is widely held to be an important mode of operation in the cortex (45, 46, 47) but not previously shown how it could arise as an emergent, rather than imposed by design, network property.

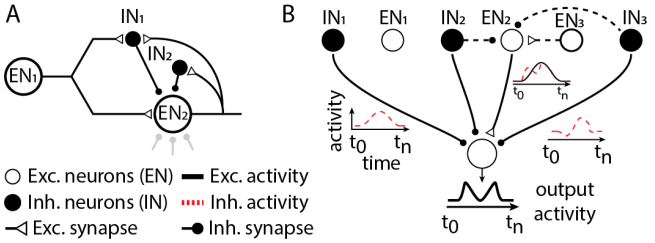

Figure 5: **Functional roles of parallel synaptic inhibition and excitation.**(**A**) Scenario when feed-forward inhibition and feedback inhibition are mediated by the same inhibitory interneuron. If multiple inhibitory interneurons provide input to EN_2 (shaded synapses below EN_2), the inhibitory control can sometimes have the properties of 'Detailed' inhibition, and sometimes have the property of 'blanket' or 'global' inhibition (see text). (**B**) A feed-forward excitatory pathway via EN_2 would lose its signal if the inhibitory signal is identical. A more diversified inhibition can help rescuing parts of the excitatory signal propagation through signal derivation.

We studied the plasticity-driven emerging functional roles for synaptic inhibition and synaptic excitation when there was no *a priori* constraint on their connectivity. The neurocomputation literature instead typically isolates excitatory from inhibitory synaptic plasticity during the learning process or considered inhibitory synapse learning as a homeostatic reaction to the learning in the excitatory synapses (48, 49, 50, 51, 52, 53). It is common practice to regard the inhibition as having a specific role, such as feed-forward, feedback or blanket inhibition. More selective inhibition has also been modeled (54), in which case it could contribute to subsets of neurons conducting more

independent computations (55, 56, 57, 58). But in recurrent networks, it is hard to see how functionally 'clean' roles of inhibition could exist, in particular since early ideas of a highly structured, 'canonical' neocortical circuitry may not apply (14) (Fig. 5A). A ground truth here could be that the division into excitatory and inhibitory neurons leads to that the inhibition can act to subtract aspects of the information (sensory or network-internal) that the network already 'knows' hence leaving 'unknown' information to be processed by other neurons in the network (Fig. 5B), both at the 'global' and at a more 'detailed' level, to use proposed terminology (48).

The neuromorphic learning strategy supports emerging, self-organizing predictive coding in cortical-like, recursive networks. Future studies can use this as a framework to study the operation of cortical networks *in vivo* more integratively. Future studies could also establish appropriate benchmarks to more systematically demonstrate the performance of neuromorphic learning networks, not the least in tasks requiring predictive coding.

Materials and Methods

Network Connectivity

We simulated two-layer fully connected recursive neuronal networks comprising both excitatory neurons (ENs) and inhibitory neurons (INs) (Fig. 1A). There were five ENs & five INs in layer 1 and four ENs & four INs in layer 2. Only the ENs and INs in layer 1 received external sensory inputs (see section *Sensory Inputs*) as excitatory synaptic connections. We did not examine autapses (self-excitatory/inhibitory connections) as they were previously observed to amplify the high-frequency parasitic oscillations within recurrent networks with these neuron specifications (8).

Neuron Model

Our previously published non-spiking linear summation neuron model (LSM) was used to compute the activity of both excitatory and inhibitory neurons. LSM is a compact model capturing the central characteristics of an H-H conductance-based neuron model (8) where the time-continuous output activity is intended to reflect the mean firing rate of a traditional spiking neuron model. In LSM, the membrane potential (A, Eq. 1) of a neuron is given by the summation of weighted (w) input synaptic activity (a), that is normalized by emulated membrane conductances (static leak and dynamic leak). The static leak (k) emulates the leak channels contributing to the resting membrane potential and is scaled by the total number of synaptic inputs (i) to the given neuron ($k = 0.25$ per synapse). The dynamic leak (τ) reflects the rate of leak towards the resting potential, normally limited by the membrane capacitance of the neuron, which was a constant ($\tau = 1/100$). The scaling effects of these membrane constants on the neuron activity under various synaptic input conditions were previously reported in (8). The neuron output activity was thresholded at a membrane potential corresponding to zero net synaptic input activity in the neuron (Eq. 2). The neuron activity of LSM is given by Eq. 1 & 2.

$$\tau \frac{dA}{dt} = \frac{\sum(w_i.a_i)}{k + \sum |w_i.a_i|} \tag{1}$$

$$if A < 0, then A = 0 \tag{2}$$

Sensory Inputs

Skin Model

A on mass-spring-damper model of a slab of skin (Fig. 1B) was used to generate the sensory input signals (*skin inputs*). This skin model was previously developed to replicate the dispersive mechanical waves that are elicited in biological skin during tactile interaction (2). The spreading mechanical waves, also studied in other experiments (59, 60, 61) create differential skin tissue movements, similar to shear forces (62), that are known to activate the skin mechanosensors, and that create extraordinary rich skin sensor information (2). The masses (circles, Fig. 1B) in this skin model were arranged in three layers superficially resembling the structural properties of human skin (epidermis, dermis and subcutaneous tissues). The masses were homogeneously distributed in a mesh-grid-like structure along each layer, and in pyramidal structures across layers (color coded as per layer, Fig. 1B). The neighbouring masses were interconnected via a network of springs and dampers (lines, Fig. 1B). In this study the skin model has a mesh size of 20×20 masses in layer 1 (400 masses), 19×19 masses in layer 2 (361 masses) and 18×18 masses in layer 3 (324 masses); interconnected with a 5770 springs and dampers. The model uses the inter-node distance, which is a representation of strain, corresponding to the spring load, as the best available proxy for representing the signal that would drive the activation of mechanoreceptors. The masses on the edges of the skin model (empty circles, Fig. 1B) were fixed in all three axes. To compute the numerical integration, the equation of motion (Eq. 3) for multiple degree-of-freedom spring-mass-damper system can be written in state-space form as in equation 4 (63, 2)

$$M\ddot{q} + C\dot{q} + Kq = f \tag{3}$$

Where M, C and K are matrices denoting mass, stiffness and damping of the whole system and f is the input force vector. q, $\dot{q}$ and $\ddot{q}$ are denoting position, velocity and acceleration of the system respectively.

$$\dot{x}(t) = Ax(t) + Bu(t) \tag{4}$$

Where x is the state vector, u is the applied input force, A is the state matrix, and B is the input matrix. Coupling equation 3 and 4, we obtain

$$M\ddot{q}(t) = -C\dot{q}(t) - Kq(t) + f(t) \tag{5}$$

Which can be written as,

$$\ddot{q}(t) = \begin{bmatrix} 0 & I \\ -M^{-1}K & -M^{-1}C \end{bmatrix} x(t) + \begin{bmatrix} 0 \\ M^{-1} \end{bmatrix} f(t) \tag{6}$$

To compute the numerical solution of the above-described state equation we used an *ode45* solver (fifth order Runge-Kutta method) in MATLAB, with a time step of 0.01 ms. Each mass within the skin model moved freely in the three-dimensional space, the matrices and vectors in the above defined state equation were adapted accordingly. The values of $M, K \& C$ are $1.0\,\mathrm{mg},\ 2.5\,\mathrm{N\,m^{-1}}$ & $5\mathrm{x}10^{-4}\mathrm{N\,s\,m^{-1}}$, as studied in (2).

Skin Inputs

To activate the skin sensors, we designed different spatial skin force patterns that were activated by defining the input force vector (f) of equation 6 as a Gaussian function with a sigma of $1ms$ (Fig 1B, insert). The force vector was three dimensional ($f = [f_x f_y f_z]$), describing the input force across all three axis of the skin. The obtained force across each spring was used as the as the output signals of the skin model, used to drive the activity of the neuronal network (*Skin Input*, Fig. 1C). The forces were given by Hooke's law ($F_s = kx$), where k is the stiffness constant of the spring and x is the rate of change in the position from equilibrium. Out of the 5770 springs available in this skin model, we use only the ten springs connected to the mass in the center of layer 1 (black mass, Fig. 1B). The responses of these ten springs were used for training and testing the networks.

Gaussian Input

As a comparison for the networks that learned from skin model inputs, which have systematic intrinsic dependencies or sensor population regularities across all inputs, we also let some networks learn from 'Gaussian inputs' that lacked such intrinsic dependencies. For each of the 10 Gaussian 'sensors', we used pseudo-random spike trains with a spiking frequency of 1-3 Hz frequency drawn from a normal distribution and convoluted using a Gaussian function to obtain a time-continuous sensory input (*Gaussian Input*, Fig. 1C). An inbuilt MATLAB function "*randi*" was used to generate the spike time distributions and "*gaussmf*" was used for the convolution of the spikes into time-continuous responses. The distribution and convolution parameters for generating the Gaussian activity were chosen to match the power and frequency components of the skin inputs (Fig. S2).

Network Training

For learning we provided the network (Fig. 1A) with a series of 1160 stimulus presentations, either sensory inputs from the skin model or from the Gaussian model (Fig. 1C). A network that learnt from the skin inputs is referred as "*skin network*" and a network that learnt from the Gaussian inputs is referred as "*Gaussian network*". For the skin networks, we used 50 unique skin activation conditions, consisting of five different activations (*indent, push, pull, slide, point push,* Fig. S1) at ten different locations on the surface of the skin model, provided in a predefined (pseudo-)random order. For the Gaussian networks, we generated non-repetitive random activity patterns across the 10 sensors. For both skin and Gaussian training inputs, individual stimulations were applied in a pseudo-random order, at an interval of 3000 ms, for a total of 1160 repetitions.

Initial Synaptic Weights and Initial Connectivity%

All the initial synaptic connections ("*initial weights*") in the network were given a weight between 0.001 and 1 (*initial weights*). No weight could ever exceed 1. As all our networks were fully connected no synapse had 0 weight. The initial weights of the whole population of synapses in the network were generated as log-normal distributions with different mean weights (μ) (values between 0.05 to 0.5) and coefficient of variation (σ_{cv}) (values between 10% - 50%). The variance of the distribution was quantified as (σ) = $(\sigma_{cv}/100) * \mu$ (Fig. S8). 'Initial connectivity%' indicated the mean weight in the network but was also a label we used to indicate the different initial weight distribution parameters (μ and σ_{cv}) (Fig. S9). Within each given parameter combination (initial connectivity%) weights were also randomized to obtain five different versions of each initial connectivity% network.

Synaptic Learning

We used the same Hebbian-inspired '*activity dependent synaptic plasticity rule*' (6) for learning synaptic weights in both excitatory and inhibitory synapses and neurons. The learning rule was formulated to reward the correlation between the individual synaptic activity (a_i) and the neuron activity (A). A positive correlation between the neuron & the synaptic activity leads to potentiation (increase) in synaptic weight and decorrelation between these activities leads to depression (decrease) in synaptic weight. For each stimulus presentation ($t_0 - t_n$), the weight change (Δw) of a synapse (i) was given by equation 7.

$$\Delta w_i = \int_{t_0}^{t_n} \{(A(t) - Th) * a_i(t)\} \ . \eta \, . \, \xi \tag{7}$$

The value of the integral ($t_n = 1000ms$) determined the magnitude of the individual synaptic weight changes.

To obtain long-term network stability, we also implemented a regulation of the synaptic plasticity that is related to the BCM rule, using a *learning polarity threshold (Th)*. The learning polarity threshold implements an effect that is related to the BCM rule and defines above what activity level the neuron becomes more likely to depress its afferent synapses, and vice versa (64, 6, 65). The Th was given by equation 8. In this case, we did implement a minor difference between the excitatory and the inhibitory synapses, which led to that the learning polarity threshold was lower for the inhibitory synapses at each given activity level of the postsynaptic neurons (Fig. S14C). This means that the probability of potentiation in the inhibitory synapses was higher for each given neuron activity level, although to a decreasing degree as the neuron activity increased. In particular at low-levels of neuron activity, such as in early stages of learning, this non-linearity enhanced the propagation of excitatory activity through the network.

$$Th = -logn(\mu, \sigma) + A(t) + A_o \tag{8}$$

The strength of potentiation/depression of an individual synaptic weight was also regulated by a learning rate (η) and a compensation factor (ξ). The learning rate was defined as an exponential decay function ($e^{-3.5}$) of the current neuron activity, limiting the rate at which synaptic weight changes occurred (Fig. S14A). The compensation factor constant is given by a sigmoid function (midpoint of 0.5 and steepness of 0.05, Fig. S14B) of current synaptic weight w_i. The compensation factor allowed the weight change of a given synapses to become higher if its current weight was low and vice versa. This factor is motivated by that the insertion of a synaptic receptor in the synaptic membrane can be regarded as a chemical reaction (the insertion and removal of synaptic receptors is handled by partly separate chemical reactions (66)), where the addition of a new channel will become less likely the higher the number of ion channels already inserted and vice versa (8). The compensation factor function was flipped for depression and potentiation of a synapse (Fig. S14B). The weight change (Δw_i) and learning polarity threshold (*Th*) were computed as moving averages across 100 stimulus presentations in order to dampen their rates of adaptation.

Excitatory Synapse Learning Signal Filter

In general, the excitatory and inhibitory synapses learned using the same Hebbian-like learning rule, based on their activity correlation with the postsynaptic neuron. But for the densest network, this proved to not work as well as for the less densely connected networks, and we therefore implemented a tweak where the excitatory synapse learning was instead based on correlation with a high-pass filtered version of the postsynaptic neuron activity. The purpose

was to make the excitatory synapse learning more selective, i.e. it would only correlate with positive changes in the postsynaptic activity. This could for example equal that the the postsynaptic activity in the dendritic spine, or the synaptic subspace underneath the excitatory synapse, would only be exposed to or only react to positive *changes* in the calcium activity of the main compartment of the neuron. Biological studies indicate that the near-synaptic calcium concentration can have different time constants than the calcium concentration in the main compartment of the neuron (67, 68, 69) and specific dynamics in the calcium concentration could impact synaptic plasticity (64). In order to achieve a high-pass filtered version of the postsynaptic activity (A), with which the excitatory synapse activity was correlated to obtain a net weight change, we multiplied that activity with an exponential function (e^x) (Fig. 4C) with different order x. This filter was applied only on excitatory synaptic activity (a_i) during the learning phase, in the analysis of Figures 4C, D, S15, S16.

Network Performance (Post-learning)

To evaluate the learning performance of the networks studied, we compared the generalization and the robustness capabilities of the skin networks and the Gaussian networks (Fig. 2). In order to test the generalization, we quantified the classification accuracy across five naive skin stimuli (Fig. S1F - J) and 11 force impulse skin stimuli (Fig. S3), neither of which were used during the learning process (Fig. 2D, F). In order to test the robustness capabilities we quantified the classification accuracy across the naive and force impulse input, by randomly removing two sensor input synapses, corresponding to 20% of the total sensor input to the network. The classification performance was quantified for four noise levels, where a random noise of a given signal-to-noise ratio (*snr*) was added to the activities of each neuron. We reported the average classification performance for 10 different repetitions of each noise level. The classification accuracy for each noise level was further reported for five different skin & Gaussian networks, *i.e.* networks that had five different random initial weights (within the constraints indicated by the initial connectivity% label), and the distribution of the classification performance across these random initial weights was reported.

Statistical Analysis

Weight change

Weight change is defined as the difference between a the initial weight of a synapse (pre-learning) and its end-weight (post-learning) as given by equation 9. The average synaptic weight changes across all the neurons were reported in Fig. 3F-I, S13, S12, S16.

$$WeightChange = \mu(EndWeight - InitialWeight) \tag{9}$$

Cross-correlation

The correlation index measure was used to compute the similarity in the neuronal activities during test inputs. The correlation between two neurons was computed with an inbuilt MATLAB function "*xcorr*" (with zero lag), which produces values from 0 (uncorrelated) to 1 (identical). This pairwise cross correlation was calculated across all neuron pairs and the average value was reported (Fig. 4A-B, S17, S15).

Frequency analysis

A continuous wavelet transform (using an inbuilt MATLAB function "*cwt*") was performed in order to define the frequency composition of the input sensory responses over time. The wavelet transform was used to extract the power of each frequency band as a function of time for the time-continuous responses of the sensors. Here, we reported (Fig. S2), for each frequency band, the maximum power of each sensor across ≈ 1160 stimulus presentations.

Principal component analysis (PCA)

Principal component analysis was performed on the actvitiy of the excitatory neurons using an inbuilt MATLAB function *pca*. The pca function projects the neuron activity onto principal component space (new set of variables, Principal Components (PCs)) that explain the high dimensional input data on fewer output dimensions while encompassing the maximum preservation of information in the input data. The product between the neuron activity and PC coefficients results in "*PC scores*" that represent the sensory signals in PC space (Fig. 2C, E).

Classification

To quantify the classification accuracy across different skin inputs (Fig. 2D, F) we used a linear tree classifier. The excitatory neuron population activity for each given skin input at each defined level of network noise was projected onto the first PC and the PC scores (see section above) were used as input observations to the classifier. Each skin input was repeated for 50 times, where the neuronal noise resulted in different responses for each repetition. The data to the classifier was binned into 5 classes while testing the 5 naive skin inputs (50 repetitions x 5 classes = 250 observations), and 11 classes while testing the 11 force impulse inputs (50 repetitions x 11 classes = 550 observations). As each response consisted of 3000 time steps, the classifier had 3000 predictors for each observation. The classifier was trained and tested using a 5-fold cross-validation, which was repeated for 100 iterations to ensure robustness. This analysis was performed using a Matlab toolbox "*Classification Learner*".

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Contributions

U.B.R. and H.J., designed and performed the research.

Competing Interests

The authors declare that they have no competing interests.

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