

Bacterial mechanosensing: the force will be with you, always

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Abstract

Whether bacteria are in the planktonic state, free-swimming or free-floating in liquid, or in the biofilm state, sessile on surfaces, they are always subject to mechanical forces. The long, successful evolutionary history of bacteria implies that they are capable of adapting to varied mechanical forces, and likely even actively respond to mechanical cues in their changing environments. However, the sensing of mechanical cues by bacteria, or bacterial mechanosensing, has been under-investigated. This leaves the mechanisms underlying how bacteria perceive and response to mechanical cues largely unknown. In this Review, we first examine the surface-associated behavior of bacteria, outline the clear evidence of bacterial mechanosensing and summarize the role of flagella, type-IV pili, and envelope proteins as potential mechanosensors, before presenting indirect evidence for mechanosensing in bacteria. The general themes underlying bacterial mechanosensing that we highlight here may provide a framework for future research.

Keywords: bacterial mechanosensing, rotating flagella, retraction of type-IV pili, envelope proteins

Introduction

To survive and develop, eukaryotic cells have to adapt to a host of mechanical cues from the environment, such as matrix rigidity, substrate topography and fluid flow. Numerous studies have been conducted to understand how eukaryotes sense and respond to mechanical cues, thus using both physical and biological

30 perspectives to establish the field of cellular mechanosensing (Cheng et al., 2017; Luo et al., 2013; Wang
31 and Thampatty, 2006). Mechanosensing is identifiable when there is a biological response – *e.g.* signaling,
32 change in gene expression, adaptation of protein function – in response to a mechanical cue, and varying
33 the mechanical cue produces a change in the biological response.

34 Bacteria are well-known to respond to some types of mechanical cues: internal and external
35 mechanical cues help to set bacterial size and shape (Si et al., 2015; Tuson et al., 2012) and changes in
36 membrane tension can be responded to by mechanosensitive channels in the bacterial membrane (Booth,
37 2014; Haswell et al., 2011). Nevertheless, far more is known about eukaryotic mechanosensing than is
38 known about whether, and how, bacteria respond to external mechanical cues by actively regulating
39 biological processes. In part, this may be because bacterial mechanosensing has been under-investigated.
40 However, bacteria have to negotiate and adapt to a wide variety of mechanical environments, in which
41 mechanical characteristics are dynamical, not static (Persat et al., 2015b). Questions of mechanosensing
42 are especially, although not exclusively, interesting for bacteria that are attached to surfaces. In nature,
43 most bacteria live on surfaces and experience more mechanical stresses, and over a greater range of values,
44 than do bacteria in fluid suspension. Furthermore, many surface-attached bacteria develop into biofilms,
45 interacting communities of microbes bound together in a matrix made up of polymers and proteins.
46 Biofilm development is a regulated, sequential process; here, a system consisting of many bacteria
47 encounters mechanics that is different from that encountered by non-biofilm bacteria (Trejo et al., 2013).
48 It is plausible, although it has not been demonstrated, that changes in the mechanical environment
49 experienced by bacteria in biofilms could serve as a regulatory cue or checkpoint.

50 Recent work has started to reveal cases of bacterial mechanosensing. For two specific types of
51 bacteria (*Escherichia coli* and *Pseudomonas aeruginosa*) there is direct evidence for mechanosensing in
52 the form of a biological activity that has been measured to vary specifically with varying mechanical input
53 (Alsharif et al., 2015; Chawla et al., 2017; Lele et al., 2013; Rodesney et al., 2017). For *E. coli*, *P.*
54 *aeruginosa*, and many other species, there is also a great deal of indirect evidence for mechanosensing in
55 that a biological response is triggered when bacteria encounter a mechanical cue. Such indirect evidence
56 largely takes the form of surface-sensing or attachment-dependent behaviors (O'Toole and Wong, 2016;
57 Tuson and Weibel, 2013). Given the widespread importance of mechanosensing in eukaryotic cells and
58 the very large body of indirect evidence for bacterial mechanosensing, it is very likely that
59 mechanosensing is widespread among many species of bacteria.

60 In this Review, we give a brief overview of what is already known about surface-sensing and
61 attachment-dependent behavior of bacteria. Then, we briefly summarize the best-studied bacterial
62 mechanosensory elements and the few cases, for which mechanosensing has been clearly shown to occur
63 for bacteria, wherein a mechanical cue leads directly to a biological response. Notably, most of these cases
64 involve a bacterial motility appendage driven by a motor, suggesting that motor response may be a
65 widespread theme in bacterial mechanosensing. Blocking the active motion of bacterial appendages results
66 in the increase of mechanical load on the associated motors, and subsequently, the mechanical signal is
67 presumably transduced into some electrical or chemical signals in the cells. Therefore, we next discuss
68 indirect evidence for mechanosensing that has been provided by studies of motility appendages and their
69 motors. Finally, we point out other findings which have not, to our knowledge, been explicitly linked to
70 mechanosensing, but we believe these findings provide additional indirect evidence for bacterial
71 mechanosensing.

72

73 **Setting the Stage**

74 **Size and force regime**

75 Bacterial cell bodies are typically on the order of one μm in extent in any direction, and therefore
76 any mechanosensing that requires the entire cell surface, or a significant fraction thereof, ought to be
77 sensitive to mechanical cues or variation on the scale of about one μm . However, bacterial appendages
78 (such as the flagellum and pili shown in Fig. 1A), which have been implicated in mechanosensing and can
79 attach to materials with their tips, are about five to eight nm in diameter in the case of pili (Craig et al.,
80 2004) and about 20 nm in diameter in the case of flagella (Macnab, 2003); this suggests that
81 mechanosensing that uses flagella or pili might be sensitive to mechanical cues or variation on length
82 scales much less than a micron. However, while they are thin, both flagella and pili can have lengths equal
83 to or greater than that of the bacteria themselves; this suggests that these appendages might be capable
84 probes of mechanical cues or variations occurring over length scales greater than a micron. Membrane
85 proteins (see inset to Fig. 1A), which have also been implicated in mechanosensing, are also
86 characteristically a few nanometers in size. This may suggest that membrane proteins would be sensitive
87 to mechanical cues that occur on the length scale of nanometers, if they have a portion that extends past
88 the cell envelope to act as a localized mechanosensor. However, this would not be the case if, as seems

89 likely to us, membrane proteins require deformation of the cell envelope to activate mechanosensing. Not
90 enough is known about bacterial envelope proteins to make declarative statements about this.

91 Swimming bacteria, driven by rotating flagella, typically are in conditions with a low-Reynolds-
92 number, i.e. viscous forces dominate over inertial forces (Purcell, 1977). In contrast, the motion twitching
93 bacteria, which move along a surface powered by extension and retraction of pili, can have ballistic
94 characteristics on short timescales, indicating that they are in a high-Reynolds-number, inertia-dominated
95 scenario on some timescales (Bisht et al., 2017). A single pilus motor can generate a force greater than
96 100 pN (Maier et al., 2002), and a single flagellum motor can generate a torque of a few thousand pN nm
97 (Berg, 2003; Lowe et al., 1987).

98 **Surface-sensing**

99 Bacteria are active swimmers rather than passive colloid particles. When they contact surfaces, adhesins
100 allow them to attach (Jarrell et al., 2011). Many different types of bacteria have adhesins, and many
101 bacteria express more than one type of adhesin (Cooley et al., 2013; Jarrell et al., 2011). Adhesin types
102 include bacterial appendages (pili, flagella and curli), proteins, and extracellular polymers (Fig. 1). The
103 diversity of these attaching mechanisms, and the redundancy provided by having multiple adhesin types
104 for a single organism, indicate that the ability to attach to surfaces is critical for bacteria. A stable
105 attachment onto surfaces is also important for most of the cases of bacterial mechanosensing that are
106 demonstrated by the direct evidence discussed below (Alsharif et al., 2015; Rodesney et al., 2017), and is
107 likely important for many more.

108 Many species of bacteria initiate biological responses when they have attached to a surface (Belas
109 and Suvanasuthi, 2005; Gode-Potratz et al., 2011; Li et al., 2012). One of the major changes in a
110 bacterium's environment when it transitions from being suspended in a fluid to being attached to a
111 substrate is a change in the mechanical characteristics of the environment. Thus, the widespread
112 observation that bacteria initiate signaling and undergo phenotypic changes – *i.e.*, the bacteria show a
113 biological response - upon coming out of fluid suspension to attach to a solid surface, is itself suggestive
114 of mechanosensing.

115

116 **Attachment-dependent behavior**

117 Perhaps the most striking attachment-dependent behavior of bacteria is biofilm development. The sessile
118 bacteria embedded in biofilms have different patterns of gene expression, metabolism, and many other
119 properties, than their planktonic (*i.e.*, free-swimming or free-floating) counterparts (Flemming et al., 2016;
120 Wang et al., 2015b).

121 Although our recent work has shown that biofilms need not necessarily develop only from single
122 cells (Kragh et al., 2016), the vast majority of studies have focused on the standard model of biofilm
123 development, which begins with planktonic bacteria approaching and adhering to surfaces (Joo and Otto,
124 2012; O'toole, 2003). This is the initial step for bacteria to switch from a motile to a sessile life.

125 Biofilm formation is regulated by a variety of signals that control modulations of microbial biology
126 (O'Toole et al., 2000). Besides biological and chemical cues, there are also potential mechanical cues
127 present during biofilm formation (Fig. 1). During biofilm initiation, swimming bacteria may detect
128 mechanical stimuli through initial surface contact and, after attaching to surfaces, bacteria experience an
129 adhesion force with the surface, substrate stiffness and topography, as well as shear that can vary with
130 surface motility and with changing fluid flow. Macroscopic biofilms exhibit viscoelastic behavior, and
131 external force - *e.g.* from shear flow - can cause structural deformation and changes in the mechanics of
132 biofilms over time (Guélon et al., 2011; Karimi et al., 2015).

133 A second type of attachment-dependent behavior is surface motility. Bacteria may move laterally on
134 the surfaces to which they are attached using several modes of motility: swarming, twitching, gliding and
135 sliding (Harshey, 2003) (Fig. 2). Swarming is the collective movement of cell clusters, powered by
136 rotating flagella, and usually takes place on soft agar plates in the laboratory (Kearns, 2010). Twitching is
137 a flagella-independent process, in which single cells or colonies move by pulling themselves along via the
138 extension and retraction of type-IV pili (Merz et al., 2000). Gliding is an active surface-motility mode
139 found in some bacterial species that does not involve pili (Gibiansky et al., 2013). Finally, sliding or
140 spreading is surface translocation powered by the expansive forces that result from cell growth, which
141 does not require an active motor (Harshey, 2003). Of the surface motility modes identified, the passive
142 ones of sliding and spreading appear the least likely to be linked to bacterial mechanosensing, which
143 generally involves functions of active motors and envelope proteins, as discussed below. Sliding or
144 spreading does not use active motors and there is no good reason, to our knowledge, to believe that forces
145 associated with these very slow motility modes will have any appreciable effect on envelope proteins
146 beyond that of surface adhesion itself.

147

148 **Cast of Characters**

149 **Envelope proteins and motility appendages driven by motors**

150 In the little that is known about bacterial mechanosensing, a widespread theme is the importance of
151 motility appendages and their associated motors.

152 Bacterial flagella are rotating, rigid helices that propel individual bacteria to swim in bulk liquid, or
153 cell clusters to swarm on surfaces (Harshey, 2003; Kearns, 2010). The flagellar motor is composed of
154 membrane-embedded stators and a transmembrane rotor (Berg, 2003) (Fig. 3A). Flagellar stators employ
155 an ion-motive-force, typically an H^+ or Na^+ -gradient-generated motive force (PMF or SMF) to drive the
156 rotor (Chevance and Hughes, 2008). Some bacteria contain more than one set of stator proteins. For
157 instance, *P. aeruginosa* uses two H^+ -powered stator sets - MotAB and MotCD (Kuchma et al., 2015), and
158 *Shewanella oneidensis* has both a H^+ -powered stator (MotAB) and a Na^+ -powered stator (PomAB)
159 (Paulick et al., 2015).

160 Type-IV pili are retractable helical filaments. They elongate by polymerization, adhere to a substrate,
161 and retract by depolymerization of the major pilin subunit (PilA). Here, elongation and retraction are
162 powered by the two cytoplasmic ATPases, PilF/B and PilT, respectively (Fig. 3B). The successive
163 extension and retraction of type IV pili drive bacterial twitching motility, independent of flagella (Merz
164 et al., 2000).

165 In addition to the importance of motor proteins, envelope proteins have also been identified as
166 important for bacterial mechanosensing. The bacterial cell envelope is composed of the inner cell
167 membrane and the cell wall, as well as, in the case of Gram-negative bacteria, the outer membrane.
168 Envelope proteins are embedded directly in the bacterial cell envelope and not incorporated in motility
169 appendages or motors. If the cell envelope is distorted, either as a result of adhesion to the surface (Fig.
170 1B) or by some other force, such distortion could be transmitted to a mechanosensitive envelope protein,
171 thereby providing a mechanical signal that is transduced by the protein into a biological signal. In this
172 context, it is noteworthy that the mechanical stiffness of bacterial cells has been found to be tightly
173 regulated (Text Box 1).

174 In *E.coli*, the CpxA-CpxR two-component system is thought to sense the deformation of the cell
175 membrane (Fig. 4C). When membrane stress increases, the outer membrane protein NlpE activates the
176 first component CpxA, an inner membrane protein. Next, CpxA undergoes autophosphorylation and
177 transfers its phosphate groups to the cytoplasmic response-regulator protein CpxR, the second component

178 in the pathway. Then, phosphorylated CpxR activates transcription of target genes (Otto and Silhavy,
179 2002).

180 Furthermore, recent work indicates that *P. aeruginosa* may use the envelope protein PilY1 as a
181 mechanosensor for surface-sensing (Luo et al., 2015; Siryaporn et al., 2014). PilY1 has some structural
182 resemblance to the mechanically-sensitive von Willebrand Factor A (VWFa) domain (Kuchma et al.,
183 2010). The VWFa domain is widely found in higher eukaryotes and VWF proteins can be deformed by
184 shear forces (Colombatti and Bonaldo, 1991; Springer, 2014). The VWFa domain of PilY1 in *P.*
185 *aeruginosa* has also been found to play an important role in surface-associated behaviors, *e.g.*, swarming
186 motility (Kuchma et al., 2010).

187 The above envelope proteins in *E.coli* and *P. aeruginosa* are often found to be linked to bacterial
188 virulence against host cells (Shimizu et al., 2016; Siryaporn et al., 2014), which will be discussed later.

189

190 **Chemical products**

191 To date, many of the identified biological responses of bacteria to mechanical inputs have been in the
192 form of either increased intracellular cyclic diguanylate (c-di-GMP) or increased production of virulence
193 factors (Alsharif et al., 2015; Rodesney et al., 2017; Siryaporn et al., 2014). C-di-GMP is a second
194 messenger that is widespread among many types of bacteria. It controls, among other things, surface-
195 associated behaviors such as biofilm formation (Jenal et al., 2017). Generally, bacteria in biofilms have a
196 higher c-di-GMP concentration than planktonic counterparts, as bacteria use an elevated c-di-GMP level
197 to stimulate the production of adhesins and exopolysaccharide matrix in biofilms (Hengge, 2009). In
198 surface-associated *P. aeruginosa*, when c-di-GMP level is high, the MotAB stator (which cannot support
199 swarming motility) can displace the MotCD stator (which promotes swarming motility) from the motor,
200 thereby repressing bacterial swarming and promoting biofilm formation on surfaces (Baker et al., 2016;
201 Kuchma et al., 2015).

202 Virulence factors are molecules produced by microbes that help them to invade and injure host
203 cells; examples are pyocyanin and hydrogen cyanide generated by *P. aeruginosa* (Siryaporn et al., 2014).
204 Both pyocyanin and hydrogen cyanide can easily penetrate biological membranes. Pyocyanin has shown
205 to inactivate catalase and disrupt calcium homeostasis in human epithelial cells, and cyanide can inhibit
206 cellular aerobic respiration (Lau et al., 2004; Lenney and Gilchrist, 2011). Notably, both c-di-GMP and

another widespread, multifunctional second messenger with many roles, cyclic adenosine monophosphate (cAMP), are involved in virulence regulation (McDonough and Rodriguez, 2012).

Action: clear-cut cases of bacterial mechanosensing

Below, we will discuss the direct evidence for bacterial mechanosensing; we consider direct evidence to be cases, in which changes of biological responses in bacteria have been observed upon varying mechanical input. When planktonic bacteria are swimming in a fluid, changing the viscosity of the liquid environment will vary the mechanical load on rotary flagellar motors (Fig. 4A). *E. coli* can adapt to changes in the torque required to swim at a given speed by adding new force-generating units (*i.e.* stators) onto the motor (Chawla et al., 2017; Lele et al., 2013; Tipping et al., 2013). Another group found that when the viscosity of the fluid environment is increased, more *Proteus mirabilis* cells elongate to lengths greater than 35 μm - this cell length is used to define “swarmer” cells in this study (Belas and Suvanasuthi, 2005). In addition, inhibition of the rotation driven by flagellar motors, as by increasing the mechanical load imposed by the viscosity of the fluid environment, triggers differentiation into swarmer cells (Belas and Suvanasuthi, 2005). These examples show that some bacteria can sense changes in the viscosity of the liquid environment by sensing changes in the external mechanical load that acts to inhibit the rotation of their flagella.

For surface-associated *P. aeruginosa*, mechanical shear, arising from the bacterial twitching motility combined with friction-like adhesion with the surface, was found to act as a mechanical cue to increase production of the intracellular signal c-di-GMP, which can initiate biofilm formation (Rodesney et al., 2017). Increasing shear (from 0 up to 0.01 $\text{pN}/\mu\text{m}^2$) by varying the speed of fluid flow over surface-attached *P. aeruginosa* also correlates with increasing levels of intracellular c-di-GMP (Rodesney et al., 2017). For this mechanosensing of mechanical shear, both type-IV pili with a functional retraction motor and the envelope protein PilY1 are required (Rodesney et al., 2017), which suggests that the pilus motor and the envelope protein PilY1 may be mechanosensory elements involved in the sensing of shear by surface-associated *P. aeruginosa* (Fig. 4B). The mechanical shear yields a tension in the type-IV pili or a deformation of the bacterial cell envelope, which might be then transduced into an elevated level of c-di-GMP.

Bacterial mechanosensing of the adhesion force exerted by the surface has been found in enterohemorrhagic *E. coli* (EHEC) (Alsharif et al., 2015). EHEC causes diseases through the expression

of virulence factors, and some of these factors are controlled by a genomic pathogenicity island called the locus of enterocyte effacement (LEE). EHEC attached to a host cell or on glass coated to be more adhesive to EHEC has an increased adhesive interaction with these surfaces compared to bare glass. Alsharif *et al.* showed that such an increased adhesive interaction between EHEC and surfaces leads to an increase in LEE activation, *i.e.* an increased virulence, and they also found that enhanced shear (0.1-10 dynes/cm²) applied by varying the speed of fluid flow over the surface-associated EHEC could further elevate LEE activation (Alsharif et al., 2015). A subsequent study found that bacterial attachment to surfaces allows NlpE in EHEC cells to upregulate the type III secretion system that is encoded by LEE genes, and that CpxR binds to the *lrhA* promoter region, which encodes the transcriptional regulator LrhA to regulate the expression of LEE genes (Shimizu et al., 2016). We therefore speculate that envelope protein system NlpE-Cpx may be a mechanosensor that allows EHEC to sense adhesion force and shear, leading to the subsequent transducing of these mechanical signals to the biological response of increased virulence.

Foreshadowing: indirect evidence for bacterial mechanosensing

Responses to initial contact with surfaces

Flagellar motors

It seems very likely that flagellar rotary motors may have a mechanosensory role, in addition to the cases of *E. coli* and *P. mirabilis* swimming in variable-viscosity fluids we discussed above (Chawla et al., 2017; Lele et al., 2013; Tipping et al., 2013). Similar to increasing fluid viscosity, contact with surfaces will obstruct or inhibit flagellar rotation – this presents a possible mechanism for surface-sensing and the initiation of surface-associated behavior (Fig. 4A). Indeed, there is good experimental evidence that this may be the case for *Vibrio parahaemolyticus* (Gode-Potratz et al., 2011; McCarter et al., 1988), *Bacillus subtilis* (Cairns et al., 2013), *Caulobacter crescentus* (Hug et al., 2017) and *P. mirabilis* (Belas and Suvanasuthi, 2005).

What mechanism(s) underlie this type of putative mechanosensing process is(are) unclear. One possibility of sensing the external mechanical load acting on rotating flagella is by surface contact; this might increase the number of stators in the flagellar motor, as discussed above (Chawla et al., 2017; Lele et al., 2013; Tipping et al., 2013). A higher number of stators then may allow bacteria to sense surfaces and to initiate swarming across soft solid surfaces (Tipping et al., 2013).

The disruption of PMF and/or SMF owing to the obstruction of flagellar rotation seems another likely mechanism. This hypothesis can be supported by the following findings. It was reported that the surface contact of *C. crescentus* causes a change in the H⁺ flux through the flagellar stators; therefore, the transient pH change inside the bacteria cell might be subsequently sensed by diguanylate cyclase DgcB, which can stimulate the production of c-di-GMP to promote biofilm formation (Hug et al., 2017). Similarly, it was also found that after *Vibrio cholera* cells attach surfaces, the inhibited flagellar rotation interrupts the decreased Na⁺ flow through the flagellar motor, leading to an increase in membrane potential ($\Delta\Psi$), which might initiate the transition of surface-associated bacteria from reversible to irreversible attachment (Van Dellen et al., 2008).

Pilus motors

Type-IV pili, and specifically their retraction motors, seem likely to be involved in bacterial mechanosensing in many different types of bacteria. Similarly to inhibiting flagellar rotation, inhibiting the retraction of type-IV pili upon surface contact can also result in a biological response (Fig. 4B). For instance, when type-IV pili of *P. aeruginosa* attach to a surface and start to retract, tension is generated in the pili; this tension is mechanically transferred through PilA (the major pilin subunits) that can interact directly with PilJ (a chemoreceptor-like protein of the Pil-Chp complex). The tension in the pili is then read out by the Chp chemosensory system within cells (Luo et al., 2015; Persat et al., 2015a). The Pil-Chp system subsequently increases cAMP production, which in turn, activates virulence (Luo et al., 2015). Additional evidence comes from other work showing that type-IV pili can be co-localized with components of the Chp system to coordinate signaling leading to cAMP-dependent upregulation of virulence of *P. aeruginosa* on surface contact (Inclan et al., 2016).

Notably, the putative mechanosensor PilY1, which as discussed above is an envelope protein in *P. aeruginosa* cells, appears to be also involved in the activation of virulence that is triggered by surface-sensing. At least two groups of researchers have found that PilY1 plays a critical role in increasing the virulence of *P. aeruginosa* upon surface contact (Luo et al., 2015; Siryaporn et al., 2014). Siryaporn *et al.* found that surface contact cannot activate virulence in *P. aeruginosa* lacking PilY1, whereas loss of the VWFa domain from the PilY1 protein leads to hyperactivated virulence, even without any surface contact (Siryaporn et al., 2014). This suggests that the VWFa domain of PilY1 may be responsible for surface detection. Both type-IV pili and PilY1 can induce virulence upon surface contact, which suggests that

these two components may work inter-relatedly. This speculation is supported by other work showing that the secretion of PilY1 depends on the type-IV pili assembly system and that PilY1 signals through the type IV pilus alignment complex to activate c-di-GMP production (Luo et al., 2015). The roles of c-di-GMP are discussed above in the section “Response to mechanical cues.”

In addition to changes in virulence, changes in the motility of some surface-associated bacteria and their descendants appear to be another mechanoreponse to surface sensing. Surface-attached *P. aeruginosa* can divide asymmetrically to generate a daughter cell that remains on the surface and a second daughter cell that detaches from the surface to colonize distant sites (Laventie et al., 2019; Lee et al., 2018). Both daughter cells can use intercellular cAMP levels and type-IV pili activity to provide a “memory” that their ancestor cell had been attached to a surface and thereby promote stronger subsequent attachment and lower surface motility (Lee et al., 2018).

Moreover, some bacterial species may have more than one pathway to sense surfaces. For instance, *C. crescentus* appears to have two mechanosensory structures that are both involved in the same process, as follows. The holdfast is a nanoscopic adhesive produced by *C. crescentus*, which helps bacteria to strongly attach to surfaces and resist displacement by flow. It was found that the holdfast adapts its elastic response from initially heterogeneous to more homogeneous with increasing time after surface attachment (Hernando-Pérez et al., 2018). In addition, it has been shown that resistance to flagellar rotation owing to surface contact in fact results in the formation of the holdfast (Hug et al., 2017). Furthermore, physically blocking the retraction of type-IV pili (and thus increasing the mechanical load on the pili during retraction), was sufficient to stimulate c-di-GMP production and initiate holdfast synthesis, even in the absence of surface contact (Ellison et al., 2017). Therefore, both inhibition of the flagellar rotary motor and inhibition of type-IV pili retraction motors are involved in surface sensing in this organism. These findings also suggest that the synthesis and development of the holdfast, like other attachment-dependent bacterial behaviors, may be regulated by mechanosensing.

There are many other examples where bacterial appendages that are driven by motors have been linked to surface sensing or to surface-associated behaviors. Although in most cases, the role of the motor was not specifically probed, in combination with the evidence highlighted above, these may be taken as indirectly suggestive of mechanosensing. There is a vast primary literature on this topic and we refer to reader to recent relevant review articles for further details (Chang, 2018; Persat, 2017). In addition to the role of bacterial appendages in surface sensing, we would like to reiterate here that proteins in the bacterial envelope have also been linked to surface sensing, and as noted above, there is evidence that these

envelope proteins also have a mechanosensory role (Luo et al., 2015; Otto and Silhavy, 2002; Rodesney et al., 2017).

Responses to substrate stiffness

Much of what is known about eukaryotic mechanobiology has been identified through studies of how varying the viscoelastic properties of the substrate (i.e. substrate stiffness) affects the cell (Discher et al., 2005; Kim et al., 2009). The solid-like stiffness of a material, i.e. the resistance, or energy cost, for deforming the material and therefore the mechanical energy that can be stored in the material as a result of deformation, is measured using an elastic modulus, which can be specific to stretching, shearing, or compressing the material.

The motility of *P. aeruginosa* and of *E. coli* on a surface varies with the elasticity of that surface. For *E. coli*, this depends on the flagellar rotation, which, as we have discussed above, is likely a mechanosensor for many bacteria (Song et al., 2017). *P. aeruginosa*'s response to substrate elasticity involves c-di-GMP, which as discussed above appears likely to also be a major player in mechanoresponse, and *oprF* (Song et al., 2018). A number of groups have determined different effects of substrate stiffness on bacterial adhesion, suggesting that mechanosensing and mechanoresponse may play a role in the initial bacterial "decision" whether to remain on a surface.

For instance, for *Staphylococcus aureus*, the number density of adherent cells on the surface of polyacrylamide hydrogels (PAAM) decreased as the modulus of the gel substrate increased (Wang et al., 2016). Here, adhesion was reduced by three logarithmic scales with increasing modulus (from 17 Pa to 654 Pa). This trend was further amplified for biofilms, as the formation of biofilms on substrates decreased as the substrate modulus increased (Wang et al., 2016). In addition, another group observed that a decrease in the elasticity of polydimethylsiloxane (PDMS) (from 2.6 to 0.1 MPa) also promoted the attachment of *E. coli* and *P. aeruginosa* (Song and Ren, 2014). *E. coli* cells attached to stiff substrates can be more motile than those on soft substrates (Song et al., 2017); this difference in motility might lead to higher rates of bacterial detachment from stiff surfaces.

However, findings from another group appear contradictory to those discussed above. In this case, *S. aureus* and *E. coli* were allowed to attach to poly(ethylene glycol) dimethacrylate hydrogels, as compared to the studies discussed above which used PDMS gels, and were found to more likely adhere when the stiffness of the substrate was increased (from 44 to 6489 kPa) (Kolewe et al., 2015; Kolewe et al., 2018). In this research, the thickness of the gel substrate deposited on the glass coverslip also impacted on the

likelihood of bacterial adhesion – more bacteria attached on the thin gel (~15 μm) than the thick gel (~150 μm). The authors speculated that the very stiff underlying glass coverslip was causing the thin hydrogels to feel stiffer to the bacteria (Kolewe et al., 2018). Thus, the effective compliance of the composite material, which is made up of both the gel and the glass coverslip, is what impacts bacterial adhesion.

By what mechanism(s) bacteria respond to substrate stiffness is not known. The apparent contradictory results described above suggest that multiple factors, including the chemistry and adhesivity of the surface, may need to be disentangled from mechanical properties. For this, intensive studies about bacterial behavior on substrates that are well-controlled and systemically-varied in their elasticity, thickness, and surface chemistry and adhesivity are needed.

Responses to surface topography

Much research has shown that bacterial adhesion can be strongly influenced by topographies, ranging from nanoscale- to microscale-defined structures (Anselme et al., 2010; Song et al., 2015). Researchers have tested surfaces patterned with regular topographic features that are intended to prevent bacterial adhesion (and might therefore be used to create improved surfaces for application in medicine and industry), but several studies showed that the initially anti-adhesive topographies reversed and instead significantly increased bacterial adhesion over longer times (Friedlander et al., 2013; Wang et al., 2015a). This phenomenon was not due to the changes of the surface energy (i.e. wetting status) of the substrate after longer exposure with bacterial culture. Rather, bacteria might in fact use their flagella to explore and eventually settle into initially unfavorable topographies (Friedlander et al., 2013; Wang et al., 2015a). Since small pits and canyons could act to restrict flagellar rotation, thus providing a mechanical signal, these may constitute additional examples of bacterial mechanosensing (Fig. 1E).

Regulation of the mechanics of bacteria

The stiffness of the bacterial cell envelope will determine how much it is deformed by adhesion and/or contact forces, and, therefore, impacts the conformational change(s) in any mechanosensory envelope proteins. Recent work has shown that bacterial cell stiffness is tightly regulated by many interacting genes (Trivedi et al., 2018). This is consistent with the idea that appropriate deformation of the cell envelope and embedded envelope proteins, leading to appropriate mechanosensing and response, could provide a selective advantage for bacteria under evolutionary pressure – for example, by promoting

the development of biofilms which can help protect bacteria from predators (Joubert et al., 2006; Matz et al., 2008).

Dependence on biofilm properties on the mechanical shear imposed during growth

Many studies have shown that biofilms grown under conditions of high fluid shear are more elastic and denser in polymers and proteins than biofilms of the same bacterial strain grown under low fluid shear (Araújo et al., 2016; Fonseca and Sousa, 2007; Herbert-Guillou et al., 2001; Lemos et al., 2015; Peyton, 1996; Stoodley et al., 2001). This adaption allows biofilms to have more cell-surface and cell-cell attachment structures and to be more resistant to the detachment caused by fluid shear (Araújo et al., 2016; Lemos et al., 2015).

To our knowledge, the underlying mechanism(s) by which biofilm mechanics and composition are altered by the fluid shear conditions under which they are grown is not known. We suggest that this phenomenon may reflect the effects of mechanosensing by bacteria either early in biofilm formation and/or within the matrix of the maturing biofilm itself. This idea is consistent with other findings, discussed above, which show that the widespread second messengers c-di-GMP and cAMP could be activated by mechanosensing. Among many other things, these intracellular signals regulate the production of matrix polymers and proteins that contribute to biofilm elasticity. For example, c-di-GMP stimulates the synthesis and secretion of the alginate and Pel exopolysaccharides that can be major components of the matrices of *P. aeruginosa* biofilms (Hengge, 2009). To study the underlying links between the higher elasticity and density of biofilms when grown under high shear and the possible causative role of a higher c-di-GMP and/or cAMP production, mutants that are deficient in the generation of c-di-GMP and/or cAMP could be used to measure how they vary with shear. We hypothesize that biofilms from such mutants will not exhibit a dependence on elasticity and density with the shear applied during growth. Alternatively, c-di-GMP/cAMP levels in biofilms could be measured, *e.g.* using fluorescent reporter proteins, *in situ*, when different shears are applied.

Conclusions

Bacterial mechanosensing allows bacteria to adapt to mechanical cues from their dynamic environments in which they live; adapting to changing mechanical environments and responding to mechanical cues is likely of great importance to bacterial survival and evolution. In bacterial mechanosensing, active motors

and envelope proteins serve as mechanosensors and trigger biological responses, with increased c-di-GMP and cAMP signaling and increased virulence being prominent examples. However, very little is known about the molecular pathways leading from mechanical inputs to biochemical signals within bacterial cells. Furthermore, as we outline above, there is a plethora of indirect evidence for bacterial mechanosensing. Thus, bacterial mechanosensing is an emerging field with a great deal left to be further investigated. Here, interdisciplinary collaborations, including the fields of physics, chemistry, molecular microbiology, and engineering are likely to be fruitful. We anticipate that an increased understanding of this aspect of bacterial cell biology will allow the development of novel approaches to manipulating bacteria, both to control unwanted infections and contamination, and to promote beneficial processes where desired.

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647 **Figure legends**

648

649 **Fig.1.** The mechanics bacteria could experience upon attaching to a surface. (i) Adhesins, including pili,
650 flagella, envelope proteins (see inset; OM: outer membrane. IM: inner membrane) and extracellular
651 polymers, allow bacteria to attach on surfaces. (ii) The flow of surrounding fluid generates shear force on
652 surface-attached bacteria. The pili and adhesive polymers help to prevent bacterial detachment from the
653 surface; the cell envelope may also deform due to shear (exaggerated in this cartoon for visibility). (iii)
654 The bacterial cell is subjected to adhesion forces (e.g. polymer-mediated adhesion, electrostatic, or van
655 der Waals forces) from the surface, leading to a deformation of the cell envelope (exaggerated in this
656 cartoon for visibility). (iv) Bacteria encounter substrates of different stiffnesses that deform differently in
657 response to adhesion forces; this can impact the surface area of the bacterial cell envelope that is in contact
658 with the substrate. (v) Surface topographies may affect bacterial adhesion. (vi) When bacteria are
659 embedded in a bulk material, growing cells experience pressure that depends on the modulus of the
660 surrounding material.

661

662 **Fig. 2.** Modes of bacterial motility on a surface. (A) Swarming motility is a multicellular movement
663 powered by flagella that are rotating counterclockwise (CCW). (B) Twitching motility is a surface
664 movement exerted either by a single bacterium or groups of bacteria. Twitching is powered by extension
665 and retraction of type-IV pili. (C) Gliding motility is driven by motor proteins, which move within the cell
666 along a helical track. The motors remain fixed positions with respect to the substrate, thereby forming focal
667 adhesion complexes, which help to propel the cell body to move forward using a CCW rotation. (D)
668 Sliding motility is a passive surface movement that is driven by cell growth.

669

670 **Fig.3.** Schematic illustration of bacterial motility appendages that have been implicated in
671 mechanosensing. (A) The flagellum consists of a basal body, hook, and filament. The basal body is
672 embedded in the inner and outer membranes and is composed of L-, P-, MS-, and C-rings. The hook
673 connects the helical filament to the basal body. The flagellar rotation is powered by a H⁺- or Na⁺ -driven
674 motor, which consists of a rotor (C-ring) and stators. The scheme has been adapted with permission from
675 (Pallen and Matzke, 2006). (B) The type-IV pilus filament is mainly composed of pilin subunits called
676 major pilins (PilA in *P. aeruginosa*). Prepilin is cleaved by PilD, and the so processed pilin subunits are
677 assembled by PilG/C into the pilus filament, which emerges from the bacterium body through PilQ. The

ATPase proteins PilF/B and PilT mediate pilus polymerization (extension) and depolymerization (retraction), respectively. The scheme has been adapted with permission from (Maier and Wong, 2015).

680

Fig.4 Bacterial mechanosensing elements and potential pathways and responses to mechanical inputs. (A) Flagella. When bacteria are swimming, the increase of the viscosity of the liquid environment or contact with substrate surfaces inhibits flagellar rotation. This may increase the amount of stators in the flagellar motor to trigger swarmer-cell differentiation and interrupt the proton or sodium ion flux through the stators to stimulate or initiate biofilm formation. (B) Type-IV pili. Upon surface contact, the inhibition of pilus retraction generates tension in the pili, which is sensed by the Chp system, leading to cAMP-dependent upregulation of virulence. Shear stresses applied on the surface-attached bacteria also generate tension in the pili during pilus retraction, which elevates the level of c-di-GMP. (C) Envelope protein. The adhesion force exerted by the surface and the shear stress yield a deformation of bacterial cell membrane, which is sensed by the outer membrane protein NlpE, triggering the signal transduction through the CpxA-CpxR two-component system. CpxR is then involved in virulence activation. OM: outer membrane. IM: inner membrane.

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