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Zeroing Neural Networks

Finite-time Convergence Design, Analysis and Applications





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Zeroing Neural Networks

Finite-time Convergence Design, Analysis and Applications

Lin Xiao Hunan Normal University

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<u>Figure</u> <u>3.1</u>	Transient behavior of $U(t)$ synthesized by GNN model (3.2) starting with 8 randomly generated initial states under the condition of $\gamma = 1$.
<u>Figure</u> <u>3.2</u>	Transient behavior of $U(t)$ synthesized by OZNN model (3.3) starting with 8 randomly generated initial states under the condition of $\gamma = 1$.
<u>Figure</u> <u>3.3</u>	Transient behavior of the residual error $ A(t)U(t) - I _F$ corresponding to $U(t)$ synthesized by GNN model (3.2) and OZNN model (3.3). (a) By GNN model (3.2) and (b) by OZNN model (3.3).
<u>Figure</u> <u>3.4</u>	Transient behavior of $U(t)$ synthesized by FTZNN model (3.11) starting with 8 randomly generated initial states under the conditions of $\gamma = \kappa_1 = \kappa_2 = 1$.
Figure 3.5	Transient behavior of the residual error $ A(t)U(t) - I _F$ synthesized by FTZNN model (3.11) under the conditions of $\kappa_1 = \kappa_2 = 1$. (a) $\gamma = 1$ and (b) $\gamma = 100$.
<u>Figure</u> <u>3.6</u>	Transient behavior of the residual error $ A(t)U(t) - I _F$ synthesized by FTZNN model (3.11) under the conditions of $\kappa_1 = \kappa_2 = 10$. (a) $\gamma = 100$ and (b) $\gamma = 10^6$.
Figure	Transient behavior of the residual error

<u>3.7</u>	$ A(t)U(t) - I _{\rm F}$ synthesized by FTZNN model
	(<u>3.11</u>) using random time-varying coefficients
	under the conditions of $\kappa_1 = \kappa_2 = 1$. (a) $\gamma = 1$ and
	(b) $\gamma = 10$.
Figure	Transient behavior of NT-FTZNN model (<u>4.6</u>)
<u>4.1</u>	matrix inversion (4.9) without noise. (a) State
	solutions and (b) residual error.
<u>Figure</u>	Transient behavior of the ZNN model activated by
<u>4.2</u>	LAF for solving time-dependent matrix inversion
	$(\underline{4.9})$ with noise $z_{ij}(t) = 1$. (a) State solutions and
	(D) residual error.
<u>Figure</u> 4 3	ransient behavior of the ZNN model activated by
1.0	time-dependent matrix inversion (4.9) with noise
	$z_{ij}(t) = \hat{1}$. (a) State solutions and (b) residual error.
<u>Figure</u>	Transient behavior of the ZNN model activated by
<u>4.4</u>	SBPAF for solving time-dependent matrix inversion
	$(\underline{4.9})$ with noise $\chi_{ij}(t) = 1$. (a) State solutions and (b) residual error
T !	(D) residual error.
<u>Figure</u> 4 5	activated by VAF for solving time-dependent
1.0	matrix inversion (4.9) with noise $z_{ii}(t) = 1$. (a)
	State solutions and (b) residual error.
<u>Figure</u>	Transient behavior of residual errors
<u>4.6</u>	$\ L(t)U(t) - I\ _{F}$ synthesized by NT-FTZNN model
	(<u>4.6</u>) activated by VAF and other ZNN models
	different noise environments for solving time-
	dependent matrix inversion (4.9). (a) Noise
	$z_{ij}(t) = 0$ with $\gamma = 1$, (b) noise $z_{ij}(t) = 0.4 y_{ij}(t) $

	with $\gamma = 1$, (c) noise $z_{ij}(t) = 0.1 \exp(0.2t)$ with $\gamma = 1$ and (d) noise $z_{ii}(t) = 0.4 \cos(2t)$ with $\gamma = 1$
<u>Figure</u> <u>4.7</u>	Transient behavior of residual errors $ L(t)U(t) - I _F$ synthesized by NT-FTZNN model (4.6) activated by VAF and other ZNN models activated by different activation functions in different noise environments for solving time-dependent matrix inversion (4.9) with different values of parameter γ . (a) Noise $z_{ij}(t) = 2t$ with $\gamma = 10$ and (b) noise $z_{ij}(t) = 20$ with $\gamma = 20$.
Figure 4.8	Transient behavior of residual errors $ L(t)U(t) - I _F$ synthesized by NT-FTZNN model (4.6) activated by VAF, GNN model, IEZNN model, and other ZNN models activated by LAF, PSAF, and SBPAF under different noise environments for solving time-dependent matrix inversion (4.11). (a) $z_{ij}(t) = 1$, (b) $z_{ij}(t) = 0.5 \sin(2.2t)$, and (c) $z_{ij}(t) = 0.15 \exp(0.2t)$.
<u>Figure</u> <u>4.9</u>	Circular task tracking synthesized by the original ZNN model activated by the SBP activation function in the presence of additive noise $z_{ij}(t) = 0.35$. (a) Whole tracking process, (b) task comparison, and (c) position error.
<u>Figure</u> <u>4.10</u>	Circular task tracking synthesized by NT-FTZNN model (<u>4.6</u>) in the presence of additive noise $z_{ij} = 0.35$. (a) Whole tracking process, (b) task comparison, and (c) position error.
<u>Figure</u> <u>4.11</u>	Physical comparative experiments of a butterfly- path tracking task generated by different ZNN models and performed on the Kinova $JACO^2$ robot manipulator when disturbed by external noise. (a)

	Failure by SBPAF activated ZNN and (b) success by NT-FTZNN.
<u>Figure</u> <u>5.1</u>	Simulative results using FPZNN model (5.4) with SBPAF when solving TVMI (5.1) of Example 1 with $k = 1.5$. (a) State solution $U(t)$ and (b) residual error $ Y(t) _{\rm F}$.
<u>Figure</u> <u>5.2</u>	Simulative results using EVPZNN model (5.7) with SBPAF when solving TVMI (5.1) of Example 1 with $k = 1.5$. (a) State solution $U(t)$ and (b) residual error $ Y(t) _{\rm F}$.
<u>Figure</u> <u>5.3</u>	Simulative results using VPZNN model (5.9) with SBPAF when solving TVMI (5.1) of Example 1 with $k = 1.5$. (a) State solution $U(t)$ and (b) residual error $ Y(t) _{\rm F}$.
<u>Figure</u> <u>5.4</u>	Simulative results using IVP-FTZNN model (5.11) with SBPAF when solving TVMI (5.1) of Example 1 with $k = 1.5$. (a) State solution $U(t)$ and (b) residual error $ Y(t) _{\rm F}$.
<u>Figure</u> <u>5.5</u>	Residual errors $ Y(t) _F$ of FPZNN (5.4), EVPZNN (5.7), VPZNN (5.9), and IVP-FTZNN (5.11) with SBPAF when solving TVMI (5.1) of Example 1 with $\gamma = k = 1.5$.
<u>Figure</u> <u>5.6</u>	Residual errors $ Y(t) _F$ of IVP-FTZNN model (5.11) with different activation functions when solving TVMI (5.1) of Example 1 with $k = 1.5$.
<u>Figure</u> <u>5.7</u>	Simulative results using IVP-FTZNN model (5.11) with SBPAF when solving TVMI (5.1) of Example 2 with $k = 1.5$. (a) State solution $U(t)$ and (b) residual error $ Y(t) _{\rm F}$.
<u>Figure</u> <u>5.8</u>	Simulative residual errors using FPZNN (5.4), EVPZNN (5.7), VPZNN (5.9), and IVP-FTZNN (5.11) with SBPAF when solving TVMI (5.1) of

	Example 2 with different γ and k . (a) With $\gamma = k = 0.5$, (b) with $\gamma = k = 2$, (c) with $\gamma = k = 5$, and (d) with $\gamma = k = 10$.
<u>Figure</u> <u>5.9</u>	Simulative residual errors using FPZNN (5.4), EVPZNN (5.7), VPZNN (5.9), and IVP-FTZNN (5.11) with SBPAF when solving TVMI (5.1) of Example 2 with different γ , k and noises $n_{ij}(t)$. (a) With $\gamma = k = 0.5$ and $n_{ij}(t) = 0.2 Y(t) _F$, (b) with $\gamma = k = 1.2$ and $n_{ij}(t) = 0.5$, (c) with $\gamma = k = 2$ and $n_{ij}(t) = 0.5 \sin(2t)$, and (d) With $\gamma = k = 2$ and $-1 \le n_{ij}(t) \le 1$.
<u>Figure</u> <u>5.10</u>	Simulative residual errors using FPZNN (5.4), EVPZNN (5.7), VPZNN (5.9), and IVP-FTZNN (5.11) with SBPAF when solving TVMI (5.1) of Example 2 with $\gamma = k = 5$ and different noises $n_{ij}(t)$. (a) With $n_{ij}(t) = 1.2t$ and with $n_{ij}(t) = 0.8 \exp(0.2t)$.
<u>Figure</u> <u>6.1</u>	Simulative results generated by the R-FTZNN model (6.26) for solving the time-varying linear equation system with no noise. (a) The first element of the neural state $\boldsymbol{u}(t)$ and the theoretical solution $\boldsymbol{u}(t)$. (b) The second element of neural state $\boldsymbol{u}(t)$ and the theoretical solution $\boldsymbol{u}(t)$ and the theoretical solution $\boldsymbol{u}(t)$. (c) The residual error $\ A(t)\boldsymbol{u}(t) - \boldsymbol{b}(t)\ _2$ corresponding to the neural state $\boldsymbol{u}(t)$.
Figure 6.2	Simulative results generated by ZNN model (6.27) for solving the time-varying linear equation system with no noise. (a) The first element of the neural state $\boldsymbol{u}(t)$ and the theoretical solution $\boldsymbol{u}^*(t)$. (b) The second element of neural state $\boldsymbol{u}(t)$ and the theoretical solution $\boldsymbol{u}^*(t)$ and the theoretical solution $\boldsymbol{u}^*(t)$. (c) The residual error $\ A(t)\boldsymbol{u}(t) - \boldsymbol{b}(t)\ _2$ corresponding to the neural state $\boldsymbol{u}(t)$.