

An Interactively Recurrent Functional Neural Fuzzy Network with Fuzzy Differential Evolution and Its Applications

(Rangkaian Neuron Kabur Berfungsi Interaktif Berulang dengan Evolusi Pengkamiran Kabur dan Penggunaannya)

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ABSTRACT

In this paper, an interactively recurrent functional neural fuzzy network (IRFNFN) with fuzzy differential evolution (FDE) learning method was proposed for solving the control and the prediction problems. The traditional differential evolution (DE) method easily gets trapped in a local optimum during the learning process, but the proposed fuzzy differential evolution algorithm can overcome this shortcoming. Through the information sharing of nodes in the interactive layer, the proposed IRFNFN can effectively reduce the number of required rule nodes and improve the overall performance of the network. Finally, the IRFNFN model and associated FDE learning algorithm were applied to the control system of the water bath temperature and the forecast of the sunspot number. The experimental results demonstrate the effectiveness of the proposed method.

Keywords: Control; differential evolution; neural fuzzy network; prediction; recurrent network

ABSTRAK

Dalam kajian ini, rangkaian neuron kabur berfungsi interaktif berulang (IRFNFN) dengan kaedah pembelajaran evolusi pengkamiran kabur (FDE) dicadangkan untuk menyelesaikan masalah kawalan dan ramalan. Kaedah tradisi evolusi pengkamiran (DE) akan terperangkap dengan mudah di dalam optimum tempatan semasa proses pembelajaran, tetapi evolusi pengkamiran kabur algoritma yang dicadangkan boleh mengatasi kelemahan ini. Melalui perkongsian maklumat nod dalam lapisan interaktif, IRFNFN yang dicadangkan boleh mengurangkan bilangan nod peraturan yang diperlukan dengan berkesan dan meningkatkan prestasi keseluruhan rangkaian. Akhir sekali, gabungan model IRFNFN dan pembelajaran algoritma FDE digunakan untuk sistem kawalan suhu rendaman air dan ramalan nombor tompok matahari. Keputusan eksperimen menunjukkan keberkesanan kaedah yang dicadangkan.

Kata kunci: Evolusi pengkamiran; kawalan; ramalan; rangkaian berulang; rangkaian neuron kabur

INTRODUCTION

In recent years, the applications of control theory to engineering system have been widely proposed. The engineering system in which the output data is not proportional to the input data, is called a nonlinear system. Controlling a nonlinear system is more difficult than controlling a linear one. Many researchers (Chen 2010; Juang & Hsieh 2010; Lee & Teng 2000; Lin et al. 2010) have conducted experiments to prove that the recurrent neural fuzzy network can achieve good results of the tracking, control and the prediction problems in complex nonlinear systems. The neural fuzzy networks commonly employ traditional learning methods, back propagation (BP) algorithm for example, to train the network parameters (Chen & Teng 1995; Li et al. 2012; Wang et al. 2011). However, BP algorithm is easily trapped into a local optimum solution.

Many researchers (Chen et al. 2014; Juang 2002; Lin et al. 2009) introduced evolutionary optimization algorithms into the learning step of neural fuzzy network, and Genetic algorithm (GA) (Lin 2004) is one of the popular evolutionary algorithms. GA can explore the global

searching space efficiently, but the problems of the local optima trap and the premature convergence still exist. In 1995, the differential evolutionary (DE) algorithm was proposed by Storn and Price (1997). Due to its simple process, less parameters, high stability and powerful population-based stochastic search technique, the DE and modified DE algorithms get a good performance in some high-dimensional engineering problems (Neri & Tirronen 2010).

The differential evolution algorithm is a kind of greedy method, which makes it converge quickly but gets trapped into the local optimum easily. Thus, Chen et al. (2009) combined the modified differential evolution algorithm in the parameter adjustment of the neural fuzzy network, Huang et al. (2006) provided some DE strategies to choose and self-adaptively control the parameters and Gong et al. (2011) presented a family of improved DEs that attempts to adaptively select a suitable strategy.

In this paper, an interactively recurrent functional neural fuzzy network (IRFNFN) with fuzzy differential evolution (FDE) learning method was proposed for solving the control and the prediction problems. The proposed

fuzzy differential evolution algorithm can improve the disadvantage of the local optimum trap in traditional DE. Moreover, the IRFNFN can effectively reduce the number of required rule nodes by sharing the information of the nodes in the interactive layer.

FUZZY DIFFERENTIAL EVOLUTION ALGORITHM

In order to achieve the adaptive searching, we use the diversities among the individuals as the inputs to the fuzzy membership functions, which inspire the corresponding strategies to adjust the parameters of DE.

FUZZY ADAPTIVE PARAMETER ADJUSTMENT

Improved differential evolution algorithm Compared to only one scale factor F in traditional DE/rand/1 method:

$$\vec{V}_{i,G} = \vec{X}_{r_1^i, G} + F * (\vec{X}_{r_2^i, G} - \vec{X}_{r_3^i, G}), \quad (1)$$

and DE/current-to-best/1:

$$\vec{V}_{i,G} = \vec{V}_{i,G} + F * (\vec{X}_{best,G} - \vec{X}_{i,G}) + F * (\vec{X}_{r_1^i, G} - \vec{X}_{r_2^i, G}). \quad (2)$$

We add an additional scale factor for more precisely controlling the convergence speed and the direction of flight.

$$\vec{V}_{i,G} = \vec{X}_{r_1^i, G} + F_1 * (\vec{X}_{r_2^i, G} - \vec{X}_{r_3^i, G}) + F_2 * (\vec{X}_{best,G} - \vec{X}_{r_1^i, G}). \quad (3)$$

The $\vec{V}_{i,G}$ denotes the individual i in the population, where $i=1, 2, \dots, NP$, and NP is the total number of the population. G denotes the generation and r_1, r_2 and $r_3 \in (1, NP)$ are random integers but $r_1 \neq r_2 \neq r_3 \neq i$.

This new method improves the DE not easily to converge prematurely. Moreover, since there was no tractive phenomenon between these two scale factors, the new mutation method would not be trapped into a local optimum while this algorithm converging.

ASSESSMENT OF EVOLUTION STATUS

Evolutionary status is a measurement of diversity among the individuals distributed in the searching space. In each generation, a status factor f is produced, and then this algorithm adjusts the parameters F and CR in DE algorithm based on the status factor f .

In order to obtain the status factor f , the individual diversities were calculated first.

$$d_i = \frac{1}{N-1} \sum_{j=1, j \neq i}^N \sqrt{\sum_{k=1}^D (x_i^k - x_j^k)^2}, \quad (4)$$

where N and D represent the number of individuals with the dimension D and d_i is the difference degree between current individual and others.

Then, the state factor was calculated as:

$$f = (d_g - d_{min}) / (d_{max} - d_{min}), \quad (5)$$

where d_g represents the diversity of the current optimum solution and d_{min} and d_{max} represent the minimum and the maximum values among all diversities. In addition, to increase the effect of disturbance on DE, we added a random selection scheme, which provides an equal probability, $1/NP$, to randomly select an individual diversity as d_g . Then, it makes the proposed method not to use the same strategy persistently.

FUZZY STRATEGY

We took the status factor as the input of fuzzy membership function, and it inspires the strategies, S1, S2, S3 and S4, through the fuzzy inference. The followings are the fuzzy membership functions, as illustrated in Figure 1.

$$\mu_{s_1}(f) = \begin{cases} 0, & \text{if } 0 \leq f \leq 0.4 \\ 5 * f - 2 & \text{if } 0.4 < f \leq 0.6 \\ 1, & \text{if } 0.6 < f \leq 0.7 \\ -10 * f + 8 & \text{if } 0.7 < f \leq 0.8 \\ 0, & \text{if } 0.8 < f \leq 1 \end{cases} \quad (6)$$

$$\mu_{s_2}(f) = \begin{cases} 0, & \text{if } 0 \leq f \leq 0.2 \\ 10 * f - 2 & \text{if } 0.2 < f \leq 0.3 \\ 1, & \text{if } 0.3 < f \leq 0.4 \\ -5 * f + 3 & \text{if } 0.4 < f \leq 0.6 \\ 0, & \text{if } 0.6 < f \leq 1 \end{cases} \quad (7)$$

$$\mu_{s_3}(f) = \begin{cases} 1, & \text{if } 0 \leq f \leq 0.1 \\ -5 * f + 1.5, & \text{if } 0.1 < f \leq 0.3 \\ 0, & \text{if } 0.3 < f \leq 1 \end{cases} \quad (8)$$

$$\mu_{s_4}(f) = \begin{cases} 0, & \text{if } 0 \leq f \leq 0.7 \\ 5 * f - 3.5, & \text{if } 0.7 < f \leq 0.9 \\ 1, & \text{if } 0.9 < f \leq 1 \end{cases} \quad (9)$$

PARAMETERS ADJUSTMENT

F and CR are important parameters in DE, where CR is the crossover rate and $CR \in [0,1]$. Most articles set $CR=0.9$ for better use (Saruhan 2014; Simon 2013; Yang et al. 2010) and on most real world problems, $Cr = 0.9$ has become the standard, which works well across a large range of problem domains (Montgomery et al. 2010). In this study, we adjusted F_1 , F_2 and CR adaptively according to f . The CR is adjusted through the following simple equation:

$$CR = 0.1 * f + 0.9. \quad (10)$$

Then, we use the adaptive strategy inspired by fuzzy reasoning to adjust F_1 and F_2 . The activation of strategy 1 is regarded as a regional search, thus we increase the value of F_1 significantly to enlarge disturbances. When strategy 2 was used, we increase F_2 significantly to make

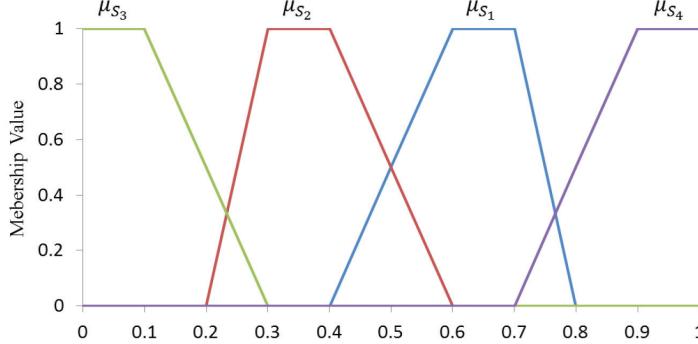


FIGURE 1. Fuzzy membership functions

TABLE 1. Strategies of fuzzy differential evolution

	F_1	F_2
strategy 1	large increase	small increase
strategy 2	small increase	large increase
strategy 3	small decrease	large decrease
strategy 4	large decrease	small decrease

the individual move in the direction toward the current global solution. All the strategies are tabulated in Table 1.

GAUSSIAN DISTURBANCE

The rapid convergence of hyper-heuristic algorithm usually makes the algorithm get trapped in a local optimum. Therefore, many researchers incorporated the Gaussian disturbance method in these algorithms (Natsuki & Hitoshi 2003). The original Gaussian disturbance used a fixed constant σ . But in this study, we reform a linearly decreased σ to increase the adaptability

$$mut(x) = x * (1 + gaussian(\sigma)) \quad (11)$$

$$\sigma = 1.0 - (1.0 - 0.1) * (g/G), \quad (12)$$

where g and G represent the numbers of the current generation and the total generation of evolution. When the current generation of the evolutionary process is getting closer to end, the occurrence probability is getting lower and near 0.1.

EXPERIMENTAL DETAILS

The performance of FDE was compared with DE/rand/1(DE) and DE/current-to-best/1(DEbest) on five well-known benchmark functions (Ali et al. 2005; Shang & Qin 2006), listed in Table 2. Among them, f_1-f_4 is single peak optimization problems, and f_5 is multimodal problems.

In our experiment, the dimension was set to 30 and the number of individuals was set to 100. The simulation results are tabulated in Table 3 and the results showed that the performance of the proposed FDE algorithm can exceed the performances of other DE algorithms.

TABLE 2. Benchmark functions

Test functions	S
$f_1 = \sum_{i=1}^D x_i^2$	[-100,100] ^D
$f_2 = \sum_{i=1}^D x_i + \prod_{i=1}^D x_i $	[-10,10] ^D
$f_3 = \sum_{i=1}^D \left(\sum_{j=1}^i x_j \right)^2$	[-100,100] ^D
$f_4 = \max_i \{ x_i , 1 \leq i \leq D \}$	[-100,100] ^D
$f_5 = \sum_{i=1}^D x_i \sin x_i + 0.1x_i $	[-10,10] ^D

TABLE 3. The function values of different DE algorithms on test functions

	Max generation	DE	DEbest	FDE
f_1	150,000	3.74E-13	2.06E-23	9.97E-90
f_2	200,000	3.74E-09	1.43E-18	1.04E-64
f_3	500,000	1.85E-10	5.25E-27	1.25E-97
f_4	500,000	3.10E-02	2.72E-15	1.18E-24
f_5	300,000	8.44E-02	5.93E-02	1.09E-14

AN INTERACTIVELY RECURRENT FUNCTIONAL NEURAL FUZZY NETWORK

In this section, we describe the structure of interactively recurrent functional neural fuzzy network (IRFNFN). The IRFNFN model adopts the interactive layer between the fuzzy-rule layer and the consequent layer in the recurrent functional neural fuzzy network (RFNFN). Through the

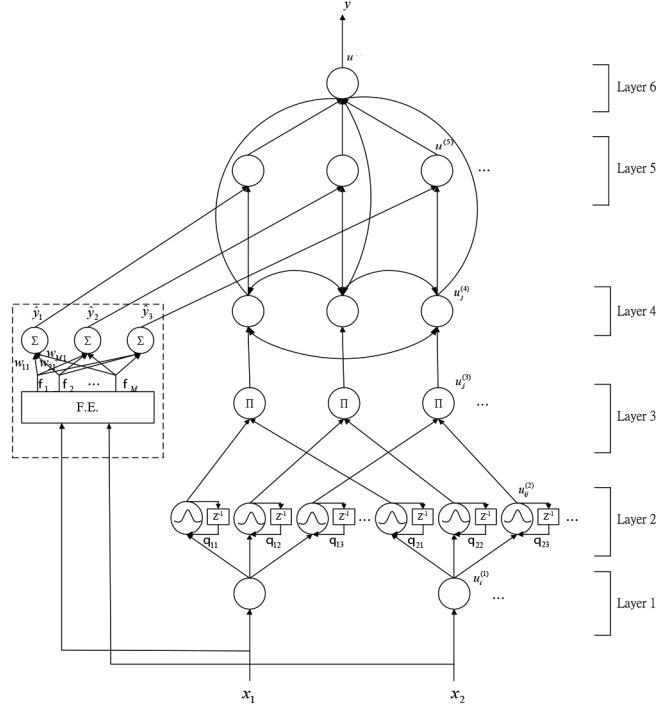


FIGURE 2. Structure of IRFNN model

information sharing among the nodes in this layer, it can improve the overall performance of the network. Figure 2 illustrates the structure of the IRFNN.

Layer 1: No function is performed in this layer. The node only transmits input values to layer 2.

$$u_i^{(1)} = x_i \quad (13)$$

Layer 2: Nodes in this layer correspond to a single linguistic label of the input variables in layer 1.

$$u_i^{(2)} = o_i^{(1)}, \quad (14)$$

$$h_{ij}^{(2)} = \exp\left(-\frac{[u_i^{(2)} - m_{ij}]^2}{\sigma_{ij}^2}\right), \quad (15)$$

where m_{ij} and σ_{ij} are the mean and variance of the Gaussian membership function, respectively. Additionally, this layer also has a recurrent relationship.

$$o_{ij}^{(2)}(t) = h_{ij}^{(2)}(t) + o_{ij}^{(2)}(t-1) \cdot \theta_{ij}, \quad (16)$$

where θ_{ij} is the feedback weight.

Layer 3: Nodes in this layer are called rule nodes and the product operator is adopted to perform the precondition part of the fuzzy rules.

$$o_j^{(3)} = \prod_i u_{ij}^{(3)}. \quad (17)$$

Layer 4: This layer is the interactive layer. Node can exchange information with other rule nodes,

$$O_i^{(4)} = \sum_{k=1}^q (\lambda_{ik}^q \cdot O_k^{(4)}(t-1)) + u_i^{(4)}, \quad (18)$$

$$\lambda_{ik}^q = \frac{C_{ik}^q}{M} (0 \leq C_{ik}^q \leq 1), \quad (19)$$

where q and M represent for the number of output and the number of fuzzy rule; C_{ik}^q is the interactive influence weight; and $O_k^{(4)}(t-1)$ - k -th is the node's previous output result.

Layer 5: Node in this layer received the output from layer 4 and the functional-link neural network (FLNN) output.

$$o_j^{(5)} = u_j^{(5)} \sum_{k=1}^M w_{kj} \emptyset_k, \quad (20)$$

where w_{kj} is the corresponding link weight of the FLNN and \emptyset_k is the functional expansion of input variables.

Layer 6: The output node acts as a defuzzifier with

$$y = \frac{\sum_{j=1}^R o_j^{(5)}}{\sum_{j=1}^R o_j^{(4)}} = \frac{\sum_{j=1}^R o_j^{(4)} \left(\sum_{k=1}^M w_{kj} \emptyset_k \right)}{\sum_{j=1}^R o_j^{(4)}}, \quad (21)$$

where R is the number of fuzzy rules; and y is the output of IRFNN model.

The parameter optimization of IRFNN is learned by the FDE learning algorithm, which has been mentioned previously.

RESULTS

In order to determine the performance of the proposed approach, we compare the experimental results with other learning methods such as DE and DEbest. The scaling factor F and the population size play a pivotal role in guiding the convergence rate. There are two alternatives in choosing these two parameters: A population of large individuals with smaller F and a small population with $F \geq 0.8$ (Montgomery 2010; Montgomery et al. 2010). In order to compromise between convergence speed and convergence probability, $F = 0.9$ is a good choice (Ronkkonen et al. 2005). In this study, we use a small population and set $F=0.9$. The default parameters are tabulated in Table 4.

TABLE 4. Default parameter setting

CR	F	F_1	F_2
0.9	0.9	0.8	0.6

The number of individuals was set to 30 and the learning was processed for 5000 generations. In addition, the root mean square error (RMSE) was used as evaluation criteria of the learning convergence. Finally, the testing results were verified by the sum of absolute error (SAE) and the formula is as follows

$$SAE = \sum_k |y_{ref}(k) - y(k)|, \quad (22)$$

where $y_{ref}(k)$ represents the expected output of network and $y(k)$ is the actual output in simulation.

In this section, the proposed model and associated learning algorithm were applied to control the water bath temperature system and forecast the sunspot number problems.

CONTROL OF WATER BATH TEMPERATURE SYSTEM

The goal of this example is to adjust the output of a water bath system to a stable target temperature using the IRFNN. The water bath plan is governed by:

$$\frac{dy(t)}{dt} = \frac{u(t)}{c} + \frac{Y_0 - y(t)}{T_R C}, \quad (23)$$

where $y(t)$ is the output temperature in Celsius; $u(t)$ is a heating flowing inward the system; Y_0 is the room temperature; C is the equivalent system thermal capacity; and T_R is the equivalent thermal resistance between the

system borders and surroundings. Assuming that T_R and C are essentially constant, we rewrite the system in (23) into discrete-time form.

$$y(k+1) = e^{-\alpha T_s} y(k) + \frac{\delta \alpha (1 - e^{-\alpha T_s})}{1 + e^{0.5(y(k)-40)}} y(k) + [1 - e^{-\alpha T_s}] y_0, \quad (24)$$

where α and δ are constant values describing T_R and C. The system parameters used in this example were $\alpha=1.0015e^{-4}$, $\delta=8.67973e^{-3}$, and $Y_0=25.0$. The input $u(k)$ was limited to 0 and 5V representing voltage units and the sampling period T_s was set to 30.

The 120 training patterns were chosen from the input-output characteristics in order to cover the entire reference output. In this experiment, we only use three fuzzy rules to control the water bath temperature system. The result of learning process is tabulated in Table 5. After the parameter optimization of IRFNN is completed by the FDE learning, we test the network performance by the testing data

$$y_{ref} = \begin{cases} 35^{\circ}C, & \text{for } k \leq 40 \\ 55^{\circ}C, & \text{for } 40 < k \leq 80 \\ 75^{\circ}C, & \text{for } 80 < k \leq 120 \end{cases} \quad (25)$$

where y_{ref} represents the targeted water temperature of the control system.

Figure 3 shows the learning curves of the FDE, DE and DEbest. In the beginning, the RMS error of FDE method was not superior to other DE algorithms. But after thousands of generation, FDE performs better while DE and DEbest methods were trapped into a local optimum. In that, for a complex network optimization problem, FDE can perform well, but it takes more time to find a better solution.

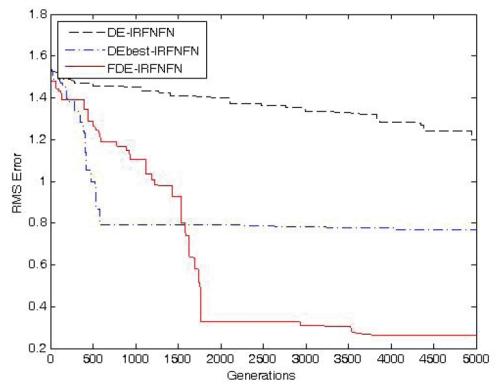


FIGURE 3. The learning curves of the FDE, DE and DEbest

TABLE 5. Performance comparison of different learning methods

	Mean RMSE	Best RMSE	Worst RMSE
DE-IRFNN	1.3561	1.224160	1.588412
DEbest-IRFNN	0.8668	0.768013	0.855330
FDE-IRFNN	0.4297	0.261764	0.579981

The testing results of water bath temperature control system by using DE, DEbest and FDE learning methods are shown in Figure 4(a)-4(c). Figure 4(d) shows the temperature difference between the desired output and the model output. Table 6 shows the sum of absolute error (SAE) by using various learning methods. In this table, we can find that the SAE of FDE has the lowest value.

FORECAST OF THE SUNSPOT NUMBER

The sunspot numbers exhibit a nonlinear pattern and those are difficult to predict. The inputs x_1 is defined as $x_1(t) = y_i^d(t-1)$, $x_2(t) = y_i^d(t-2)$ and $x_3(t) = y_i^d(t-3)$, where t represents the year and $y_i^d(t-1)$ is the sunspot number at

the t year. In this experiment, 151 data (from 1703 to 1884) were selected as the training set and the whole 302 data (from 1703 to 2004) were used as testing data. Here we use only three fuzzy rules to perform prediction problem. The experimental results using various learning methods are shown in Table 7.

Figure 5 shows the learning curves of various learning methods. In this figure, we can see that DE and DEbest have fallen into the local optimum during the learning process. In contrast, the proposed FDE can escape from the local solution after 3000 iterations. Table 8 tabulates the sum of absolute error (SAE) by using various learning methods. The results showed that the proposed method has superior performances than the others.

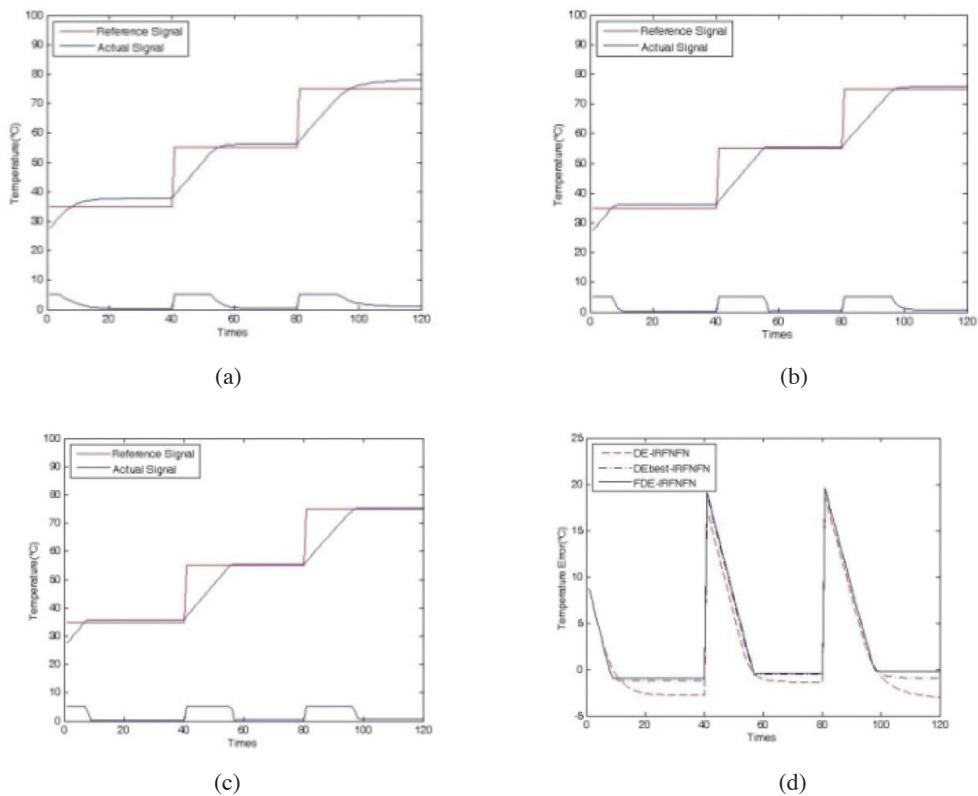


FIGURE 4. The testing results of water bath temperature control system,
(a) DE, (b) DEbest, (c) FDE and (d) temperature error

TABLE 6. The experimental result of water bath temperature control system

	DE	DEbest	FDE
SAE	474.252	422.966	404.207

TABLE 7. Performance comparison of various learning methods

	Mean RMSE	Best RMSE	Worst RMSE
DE-IRFNFN	13.8941	13.3845	14.7746
DEbest-IRFNFN	13.067	12.9121	13.4989
FDE-IRFNFN	11.9511	11.1615	12.0102

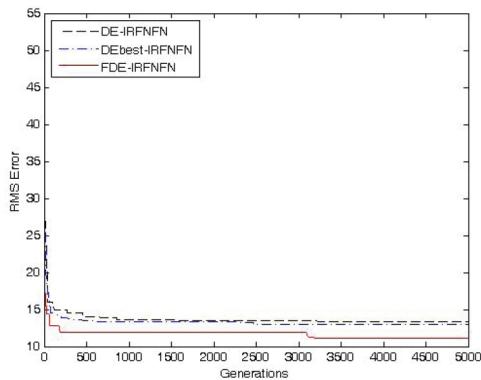


FIGURE 5. The learning curves of the FDE, DE and DEbest methods

TABLE 8. The experimental result of forecast of sunspot number

	DE	DEbest	FDE
SAE	4133.83	4174.33	3922.02

CONCLUSION

In this paper, we proposed an interactively recurrent functional neural fuzzy network with fuzzy differential evolution learning algorithm for solving control and prediction problems. The proposed fuzzy differential evolution algorithm can improve the drawback of local optimum trap in traditional DE, and the proposed IRFNN can effectively reduce the number of required rule nodes by sharing node information in the interactive layer. The experimental results proved that the fuzzy differential evolution has effectively superior performance than the other DE methods.

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