Research Article

Less Conservative Stability Criteria for Neutral Type Neural Networks with Mixed Time-Varying Delays

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Received 20 May 2013; Accepted 7 September 2013

Academic Editor: Qiankun Song

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This paper investigates the problem of dependent stability criteria for neutral type neural networks with mixed time-varying delays. Firstly, some new delay-dependent stability results are obtained by employing the more general partitioning approach and generalizing the famous Jensen inequality. Secondly, based on a new type of Lyapunov-Krasovskii functional with the cross terms of variables, less conservative stability criteria are proposed in terms of linear matrix inequalities (LMIs). Furthermore, it is the first time that the idea of second-order convex combination and the property of quadratic convex function applied to the derivation of neutral type neural networks play an important role in reducing the conservatism of the paper. Finally, four numerical examples are given to show the effectiveness and the advantage of the proposed method.

1. Introduction

During the last two decades, delayed neural networks have drawn a great deal of attention because of their extensive applications in various scientific and technical areas, such as pattern recognition, power systems, parallel computing, signal processing, finance, associative memories, mechanics of structures, and other scientific areas [1–30]. It is well known that time delay regarded as a major cause of instability and poor performance often appears in many neural networks. Therefore, the stability analysis for delayed neural networks has been investigated extensively in recent few decades. Generally speaking, studying the dynamical behavior of delayed neural networks can be mainly classified into two types: delay-independent stability and delay-dependent stability. As is known to all, delay-dependent stability criteria are less conservative than delay-independent ones when the size of time delay is small.

On the other hand, due to the complicated dynamic properties of the neural cells in the real world, there exist many neural network models such as distributed networks,

chemical reactors, and heat exchanges that cannot characterize the properties of a neural reaction process precisely. It is natural and important that these systems will contain some information about the derivative of the past state to further describe and model the dynamics of the complex neural reactions. This new type of neural networks is called neutral neural networks or neural networks of neutral type. However, many researchers have focused on the global stability of neural networks of neutral type only with constant time delay in recent years, which is very restrictive. Hence, described with neutral functional differential equations with discrete and distributed delays, these neural networks called neutral type neural networks with mixed time-varying delays have a lot of research on space. The differential expression not only defines the derivative term of the current state but also explains the derivative term of the past state. Furthermore, it is necessary to have some information about the derivative of the past state in the systems to characterize the dynamics of such complex neural reactions. Practically, neutral type phenomenon always appears in studies of automatic control,

chemical reactors, distributed networks, dynamic process including steam and water pipes, population ecology, heat exchanges, microwave oscillators, systems of turbojet engine, lossless transmission lines, vibrating masses attached to an elastic bar, and so on. For this reason, there has been a growing research interest in the study of delayed neural networks of neutral type in the recent years. Therefore, some less conservative stability criteria for neutral type neural networks with mixed time-varying delays have been reported in recently [25, 31–35]. Many methods have been proposed in these results to reduce the conservatism of the stability criteria, such as model transformation method, free-weighting matrix method, the method of constructing novel Lyapunov-Krasovskii functionals, delay decomposition technique, and weighting-matrix decomposition method. In [36], the authors derived some less conservative stability criteria by considering some useful terms and using free-weighting matrix technique. By considering the relationship between the time-varying delay and its lower and upper bound, the results obtained in [36] were improved in [37]. By constructing a new Lyapunov-Krasovskii functional and using free-weighting matrix method, some more less conservative criteria than those obtained in [37] were proposed in [38]. Further, the problems of stability analysis of neutral type neural networks with discrete and distributed delays have been investigated in [39]. By using a delay-partitioning approach, a new type of Lyapunov-Krasovskii functionals was constructed to obtain some less conservative stability criteria. However, time delay in [39] is not only constant delay, but also the delay-partitioning approach is equational; hence, this method has some limitations.

Motivated by this technique, it is the first attempt to investigate the integral nonuniform partitioning method to be extended for neutral type neural networks with mixed time-varying delays. In the paper, the reduced conservatism of Theorem 6 benefits from the construction of the new Lyapunov-Krasovskii functionals in (17), which contain some integral nonuniform partitioning method and triple-integral terms, which play an important role in the improvement of less conservative results. Secondly, a novel handling method is given to establish the relationship among $\int_{t-h}^t \dot{x}(s) S_5 \dot{x}(s) ds$, $\int_{t-h}^t x^T(s) ds$ and $x(t-h)$, which play an important role in reducing the conservatism of stability criteria further. Furthermore, compared with previous results by using the first-order convex combination property, our derivation makes full use of the idea of second-order convex combination and the property of quadratic convex function given in the form of a lemma without employing Jensen's inequality. Finally, four numerical examples are given to illustrate the effectiveness and the advantage of the proposed main results.

Notation 1. Notations used in this paper are fairly standard: R^n denotes the n -dimensional Euclidean space, $R^{n \times m}$ is the set of all $n \times m$ dimensional matrices; I denotes the identity matrix of appropriate dimensions, T stands for matrix transposition, the notation $X > 0$ (resp., $X \geq 0$), for $X \in R^{n \times n}$ means that the matrix is real symmetric positive definite (resp., positive semidefinite); $\text{diag}\{r_1, r_2, \dots, r_n\}$

denotes block diagonal matrix with diagonal elements r_i , $i = 1, 2, \dots, n$, the symbol $*$ represents the elements below the main diagonal of a symmetric matrix, and $\langle M \rangle_s$ is defined as $\langle M \rangle_s = (1/2)(M + M^T)$.

2. Preliminaries

Consider the following neural networks of neutral type with mixed time-varying delays:

$$\begin{aligned} \dot{z}(t) = & -W_0 z(t) + W_1 g(z(t)) + W_2 g(z(t-h(t))) \\ & + W_3 \int_{t-r}^t g^T(z(s)) ds + W_4 \dot{y}(t-h(t)) + J, \end{aligned} \quad (1)$$

where $z(t) = [z_1(t), \dots, z_n(t)]^T \in R^n$ is the neural state vector, $g(z(t)) = [g(z_1(t)), \dots, g(z_n(t))]^T$ is the neuron activation function, $J = [J_1, \dots, J_n]^T \in R^n$ is an external constant input vector, and $W_0 = \text{diag}\{w_{01}, \dots, w_{0n}\} > 0$, W_1, W_2, W_3 , and W_4 are the constant matrices of appropriate dimensions.

Assumption A. The time-varying delay $h(t)$ is continuous and differential function that satisfies

$$0 \leq h(t) \leq h, \quad \dot{h}(t) \leq h_D < 1. \quad (2)$$

Assumption B. For the constants δ_i^+ , δ_i^- , the nonlinear function $g_i(\cdot)$ in (1) satisfies the following condition:

$$\delta_i^- \leq \frac{g_i(\alpha) - g_i(\beta)}{\alpha - \beta} \leq \delta_i^+, \quad (3)$$

$$\forall \alpha, \beta \in R, \quad \alpha \neq \beta, \quad i = 1, 2, \dots, n.$$

Here, we denote $\bar{\Sigma} = \text{diag}\{\delta_1^+, \dots, \delta_n^+\}$, $\underline{\Sigma} = \text{diag}\{\delta_1^-, \dots, \delta_n^-\}$, $\Sigma = \text{diag}\{\max\{|\delta_1^+|, |\delta_1^-|\}, \dots, \max\{|\delta_n^+|, |\delta_n^-|\}\} = \text{diag}\{\delta_1, \dots, \delta_n\}$, $\Sigma_1 = \text{diag}\{\delta_1^+ \delta_1^-, \dots, \delta_n^+ \delta_n^-\}$, $\Sigma_2 = \text{diag}\{(\delta_1^+ + \delta_1^-)/2, \dots, (\delta_n^+ + \delta_n^-)/2\}$.

Assumption C. For given positive scalars ρ_i satisfies:

$$0 = \rho_0 < \rho_1 < \dots < \rho_l = 1 \quad (i = 1, \dots, l). \quad (4)$$

It is clear that under Assumption B, the system (1) has one equilibrium point denoted as $z^* = [z_1^*, \dots, z_n^*]^T$. For convenience, we firstly shift the equilibrium point z^* to the origin by letting $x(t) = z(t) - z^*$, $f(x(t)) = g(z(t)) - g(z^*)$; then the system (1) can be transformed into

$$\begin{aligned} \dot{x}(t) = & -W_0 x(t) + W_1 f(x(t)) + W_2 f(x(t-h(t))) \\ & + W_3 \int_{t-r}^t f^T(x(s)) ds + W_4 \dot{x}(t-h(t)), \end{aligned} \quad (5)$$

where $x(t) = [x_1(t), \dots, x_n(t)] \in R^n$ is the state vector of transformed system, $f(x(t)) = [f_1(x_1), \dots, f_n(x_n)]^T \in R^n$. It is easy to check that the transformed neuron activation function $f_i(\cdot)$ satisfies

$$\delta_i^- \leq \frac{f_i(\alpha)}{\alpha} \leq \delta_i^+, \quad f_i(0) = 0, \quad (6)$$

$$\forall \alpha \in R, \quad \alpha \neq 0, \quad i = 1, 2, \dots, n.$$

The following lemmas are introduced, which will be used in the proof of the main results.

Fact 1 (Boyd et al. [40], (Schur complement)). For a given symmetric matrix $X = X^T = \begin{bmatrix} X_{11} & X_{12} \\ * & X_{22} \end{bmatrix}$, where $S_{11} \in R^{n \times n}$, the following conditions are equivalent:

- (1) $X < 0$;
- (2) $X_{11} < 0, X_{22} - X_{12}^T X_{11}^{-1} X_{12} < 0$;
- (3) $X_{22} < 0, X_{11} - X_{12} X_{22}^{-1} X_{12}^T < 0$.

Lemma 1 (see [41]). For symmetric matrices Y_0, Y_1, Y_2 , and a vector ξ_t , Let $f(\alpha) = \alpha^2 \xi_t^T Y_2 \xi_t + \alpha \xi_t^T Y_1 \xi_t + \xi_t^T Y_0 \xi_t$ with $Y_2 \leq 0$. Then we have $f(\alpha_1) < 0$ and $f(\alpha_2) < 0 \Rightarrow f(\alpha) < 0, \forall \alpha \in [\alpha_1, \alpha_2]$.

Lemma 2 (see [42]). Let $W > 0$, and let $\omega(s)$ be an appropriate dimensional vector. Then, we have the following facts for any scalar function $\beta(s) \geq 0 \forall s \in [a, b]$:

- (1) $-\int_a^b \omega^T(s) W \omega(s) ds \leq (b-a) \xi_t^T F_1 W^{-1} F_1 \xi_t + 2 \xi_t^T F_1 \int_a^b \omega(s) ds$;
- (2) $-\int_a^b \beta(s) \omega^T(s) W \omega(s) ds \leq \int_a^b \beta(s) ds \xi_t^T F_2 W^{-1} F_2 \xi_t + 2 \xi_t^T F_2 \int_a^b \beta(s) \omega(s) ds$;
- (3) $-\int_a^b \beta^2(s) \omega^T(s) W \omega(s) ds \leq (b-a) \xi_t^T F_3 W^{-1} F_3 \xi_t + 2 \xi_t^T F_3 \int_a^b \beta(s) \omega(s) ds$,

where matrices F_i ($i = 1, 2, 3$) and a vector ξ_t independent of the integral variable are appropriate dimensional arbitrary ones.

Lemma 3 (see [43]). For any constant matrix $0 < R = R^T \in R^{n \times n}$, a scalar $r > 0$ and a vector function $x : [0, r] \rightarrow R^n$ such that the integrations concerned are well defined; then

$$\begin{aligned} & -\int_{t-r}^0 x^T(s) R x(s) ds \\ & \leq -\frac{1}{r} \left(\int_{t-r}^t x(s) ds \right)^T R \left(\int_{t-r}^t x(s) ds \right), \\ & -\int_{-r}^0 \int_{t+\theta}^t x^T(s) R x(s) ds d\theta \\ & \leq -\frac{2}{r^2} \left(\int_{-r}^0 \int_{t+\theta}^t x(s) ds d\theta \right)^T R \left(\int_{-r}^0 \int_{t+\theta}^t x(s) ds d\theta \right). \end{aligned} \quad (7)$$

Lemma 4 (see [44]). For any constant matrix $R \in R^{n \times n}$, $R = R^T > 0$, a scalar function $h := h(t) > 0$, and a vector-valued

function $\dot{x} : [-h, 0] \rightarrow R^n$ such that the following integrations are well defined:

$$\begin{aligned} & -h \int_{t-h}^t \dot{x}(s) R \dot{x}(s) ds \leq \begin{bmatrix} x(t) \\ x(t-h) \end{bmatrix}^T \begin{bmatrix} -R & R \\ R & -R \end{bmatrix} \begin{bmatrix} x(t) \\ x(t-h) \end{bmatrix}, \\ & -\frac{h^2}{2} \int_{-h}^0 \int_{t+\theta}^t \dot{x}^T(s) R \dot{x}(s) ds d\theta \\ & \leq \begin{bmatrix} hx(t) \\ \int_{t-h}^t x(s) ds \end{bmatrix}^T \begin{bmatrix} -R & R \\ R & -R \end{bmatrix} \begin{bmatrix} hx(t) \\ \int_{t-h}^t x(s) ds \end{bmatrix}. \end{aligned} \quad (8)$$

Lemma 5. Let $x(t) \in R^n$ has continuous derived function $\dot{x}(t)$ on interval $[0, h]$. Then for any matrix $Z^{n \times n} > 0$, scalar $h > 0$, the following inequality holds:

$$\begin{aligned} & -h \int_{t-h}^t \dot{x}(s) R \dot{x}(s) ds \\ & \leq -\frac{2}{h} \begin{bmatrix} \frac{1}{h} \int_{t-h}^t x(s) ds \\ x(t-h) \end{bmatrix}^T \begin{bmatrix} R & -R \\ -R & R \end{bmatrix} \begin{bmatrix} \frac{1}{h} \int_{t-h}^t x(s) ds \\ x(t-h) \end{bmatrix}. \end{aligned} \quad (9)$$

Proof. From Lemma 3, we can get

$$\begin{aligned} & \frac{1}{h} \left(\int_{t-h}^t \int_{t-h}^\theta \dot{x}(s) ds d\theta \right)^T R \left(\int_{t-h}^t \int_{t-h}^\theta \dot{x}(s) ds d\theta \right) \\ & \leq \int_{t-h}^t \left(\int_{t-h}^\theta \dot{x}(s) ds \right)^T R \left(\int_{t-h}^\theta \dot{x}(s) ds \right) d\theta \\ & \leq \int_{t-h}^t \int_{t-h}^\theta (\theta - (t-h)) \dot{x}^T(s) R \dot{x}(s) ds d\theta \\ & \leq \int_{t-h}^t \int_s^t (\theta - (t-h)) \dot{x}^T(s) R \dot{x}(s) d\theta ds \\ & = \int_{t-h}^t \left(\frac{h^2}{2} - \frac{(s-t+h)^2}{2} \right) \dot{x}^T(s) R \dot{x}(s) ds \\ & \leq \frac{h^2}{2} \int_{t-h}^t \dot{x}^T(s) R \dot{x}(s) ds. \end{aligned} \quad (10)$$

Notice that

$$\begin{aligned} & \left(\int_{t-h}^t \int_{t-h}^\theta \dot{x}(s) ds d\theta \right)^T R \left(\int_{t-h}^t \int_{t-h}^\theta \dot{x}(s) ds d\theta \right) \\ & = \begin{bmatrix} \int_{t-h}^t x(s) ds \\ hx(t-h) \end{bmatrix}^T \begin{bmatrix} R & -R \\ -R & R \end{bmatrix} \begin{bmatrix} \int_{t-h}^t x(s) ds \\ hx(t-h) \end{bmatrix}. \end{aligned} \quad (11)$$

Therefore, we get

$$\begin{aligned}
 & - \int_{t-h}^t \dot{x}(s) R \dot{x}(s) ds \\
 & \leq -\frac{2}{h} \left[\frac{1}{h} \int_{t-h}^t x(s) ds \right]^T \begin{bmatrix} R & -R \\ -R & R \end{bmatrix} \left[\frac{1}{h} \int_{t-h}^t x(s) ds \right].
 \end{aligned} \quad (12)$$

This completes the proof. $\square$

3. Main Results

In this section we will give sufficient conditions under which the system (5) is asymptotically stable.

Theorem 6. For given scalars $h > 0$ and $h_D < 1$, the system (5) with the neuron activation function $f(x(t))$ satisfying the condition (6) is asymptotically stable if there exists $P > 0$, $R_i^T = R_i > 0$ ($i = 1, 2, 3$), $Q_i^T = Q_i > 0$ ($i = 1, 2$), $S_i^T = S_i > 0$ ($i = 1, \dots, 8$), $Z_i^T = Z_i > 0$ ($i = 1, \dots, l$), diagonal matrices $G_i = \text{diag}\{g_{i1}, g_{i2}, \dots, g_{in}\} > 0$, $K_i = \text{diag}\{k_{i1}, k_{i2}, \dots, k_{in}\} > 0$, $L_i = \text{diag}\{l_{i1}, l_{i2}, \dots, l_{in}\} > 0$, ($i = 1, 2, 3$) and $M = \text{diag}\{m_{i1}, m_{i2}, \dots, m_{in}\} > 0$, ($i = 1, 2, 3, 4$), T_i ($i = 1, \dots, 5$) and F_i ($i = 1, \dots, 6$) with appropriate dimensions such that the following symmetric linear matrix inequality holds:

$$\Xi_1 = \begin{bmatrix} \Pi_0 & hF_1^T & hF_2^T & hF_3^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (13)$$

$$\Xi_2 = \begin{bmatrix} \Pi_0 + h\Pi_1 & hF_4^T & hF_5^T & hF_6^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (14)$$

where

$$\begin{aligned}
 \Pi_0 = & \left\langle 2 \begin{bmatrix} e_1 & e_7 + e_8 \end{bmatrix} P \begin{bmatrix} e_2 & e_1 - e_4 \end{bmatrix}^T \right. \\
 & + 2 \begin{bmatrix} e_2 & 0 \end{bmatrix} R_1 \begin{bmatrix} 0 & e_7 + e_8 \end{bmatrix}^T \\
 & + 2 \begin{bmatrix} e_2 & 0 \end{bmatrix} R_2 \left[h e_1 \quad e_8 \right]^T \Big\rangle_s + \begin{bmatrix} e_1 & e_1 \end{bmatrix} \\
 & \times (R_1 + R_2) \begin{bmatrix} e_1 & e_1 \end{bmatrix}^T \\
 & - (1 - h_D) \begin{bmatrix} e_1 & e_3 \end{bmatrix} R_1 \begin{bmatrix} e_1 & e_3 \end{bmatrix}^T \\
 & - \begin{bmatrix} e_1 & e_4 \end{bmatrix} R_2 \begin{bmatrix} e_1 & e_4 \end{bmatrix}^T + h \begin{bmatrix} e_1 & e_2 \end{bmatrix} R_3 \\
 & \times \begin{bmatrix} e_1 & e_2 \end{bmatrix}^T + e_2 \left(h^2 Q_1 + h^3 Q_2 \right) e_2^T
 \end{aligned}$$

$$\begin{aligned}
 & + \left\langle 2F_1^T \begin{bmatrix} e_7 & e_3 - e_4 \end{bmatrix}^T + 4F_2^T \left[h e_3 - e_7 \right]^T \right. \\
 & \quad + 6F_3^T \left[h e_3 - e_7 \right]^T \\
 & \quad + 2F_4^T \begin{bmatrix} e_8 & e_1 - e_3 \end{bmatrix}^T - 4F_5^T e_8^T - 6F_6^T e_8^T \Big\rangle_s \\
 & + e_9 (S_1 + S_2) e_9^T - (1 - h_D) e_{10} S_1 e_{10}^T - e_{11} S_2 e_{11}^T \\
 & - e_6 S_4 e_6^T + e_2 (S_3 + S_4) e_2^T - (1 - h_D) e_5 S_3 e_5^T \\
 & + e_2 \left(h S_5 + \frac{h^2}{2} S_6 \right) e_2^T - 2e_1 S_6 e_1^T + \frac{4}{h} e_1 S_6 e_7^T \\
 & + \frac{4}{h} e_1 S_6 e_8^T + \frac{4}{h^2} e_4 S_5 e_7^T + \frac{4}{h^2} e_4 S_5 e_8^T - \frac{2}{h} e_4 S_5 e_4^T \\
 & - e_7 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) e_7^T - e_7 \left(\frac{4}{h^3} S_5 + \frac{4}{h^2} S_6 \right) e_8^T \\
 & - e_8 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) e_8^T \\
 & + e_9 \left(r S_7 + \frac{r^2}{2} S_8 + \sum_{i=1}^l (\rho_i - \rho_{i-1}) r Z_i \right) e_9^T \\
 & - \sum_{i=1}^l \frac{1}{(\rho_i - \rho_{i-1}) r} e_{11+i} Z_i e_{11+i}^T \\
 & - \frac{1}{r} (e_{12} + \dots + e_{11+l}) S_7 (e_{12} + \dots + e_{11+l})^T \\
 & - \frac{2}{r^2} e_{12+l} S_8 e_{12+l}^T \\
 & + e_1 (\bar{\Sigma} K_1 - \underline{\Sigma} G_1 + L_1 \Sigma) e_2^T + 2e_2 (G_1 - K_1 + L_1) e_9^T \\
 & + 2e_3 (\bar{\Sigma} K_2 - \underline{\Sigma} G_2 + L_2 \Sigma) e_5^T + 2e_5 (G_2 - K_2 + L_2) e_{10}^T \\
 & + 2e_4 (\bar{\Sigma} K_3 - \underline{\Sigma} G_3 + L_3 \Sigma) e_6^T + 2e_6 (G_3 - K_3 + L_3) e_{11}^T \\
 & + e_1 (\Sigma M_1 \Sigma - M_2 \Sigma_1) e_1^T + 2e_1 M_2 \Sigma_2 e_9^T - e_3 M_3 \Sigma_1 e_3^T \\
 & + 2e_3 M_3 \Sigma_2 e_{10}^T - e_9 (M_1 + M_2) e_9^T \\
 & - e_{10} M_3 e_{10}^T - e_4 M_4 \Sigma_1 e_4^T \\
 & + 2e_4 M_4 \Sigma_2 e_{11}^T + e_2 (-T_1 - T_1^T) e_2^T \\
 & - e_{11} M_4 e_{11}^T - 2e_1 W_0^T T_1^T e_2^T \\
 & + 2e_2 T_1 W_1 e_9^T + 2e_2 T_1 W_2 e_{10}^T \\
 & + 2e_2 T_1 W_3 (e_{12} + \dots + e_{11+l})^T \\
 & + 2e_2 T_1 W_4 e_5^T - 2e_1 T_2 e_2^T + e_1 (-T_2 W_0 - W_0^T T_2^T) e_1^T \\
 & + 2e_1 T_2 W_1 e_9^T + 2e_1 T_2 W_2 e_{10}^T \\
 & + 2e_1 T_2 W_3 (e_{12} + \dots + e_{11+l})^T \\
 & + 2e_2 T_2 W_4 e_5^T - 2e_2 T_3^T e_9^T
 \end{aligned}$$

$$\begin{aligned}
& -2e_1 W_0^T T_3^T e_9^T + 2e_9 T_3 W_2 e_{10}^T \\
& + e_9 (T_3 W_1 + W_1^T T_3^T) e_9^T + 2e_9 T_3 W_3 (e_{12} + \dots + e_{11+l})^T \\
& + 2e_5 W_4^T T_3^T e_9^T - 2e_2 T_4^T e_{10}^T + e_9 W_1^T T_4^T e_{10}^T \\
& + e_{10} (T_4 W_2 + W_2^T T_4^T) e_{10}^T \\
& + 2e_{10} T_4 W_3 (e_{12} + \dots + e_{11+l})^T \\
& + 2e_5 W_4^T T_4^T e_{10}^T + 2e_5 W_4^T T_3^T e_9^T \\
& - 2e_2 T_5^T e_5^T - 2e_1 W_0^T T_5^T e_5^T \\
& + e_5 T_5 W_1 e_9^T + e_5 T_5 W_2 e_{10}^T + 2e_5 (T_5 W_4 + W_4^T T_4^T) e_5^T \\
& + 2e_5 T_5 W_3 (e_{12} + \dots + e_{11+l})^T - 2e_1 W_0^T T_4^T e_{10}^T, \\
\Pi_1 = & \left\langle 2(e_2 \ 0) R_1 (e_1 \ e_0)^T - 4F_2^T e_3^T - 6F_3^T e_3^T \right. \\
& \left. + 4F_5^T e_1^T + 6F_6^T e_1^T \right\rangle_s,
\end{aligned} \tag{15}$$

with

$$\langle \cdot \rangle_s = \frac{1}{2} [(\cdot) + (\cdot)^T], \quad e_i = [0_{n \times (i-1)} \ I_{n \times n} \ 0_{n \times (12+l-i)}]^T$$

$$(i = 1, \dots, 12 + l). \tag{16}$$

Proof. Consider a novel augmented Lyapunov-Krasovskii functional for the system (5) as follows:

$$\begin{aligned}
V(x_t) = & V_1(x_t) + V_2(x_t) + V_3(x_t) + V_4(x_t) + V_5(x_t) \\
& + V_6(x_t) + V_7(x_t),
\end{aligned} \tag{17}$$

where

$$\begin{aligned}
V_1(x_t) = & \xi_1^T(t) P \xi_1(t), \\
V_2(x_t) = & \int_{t-h(t)}^t \xi_2^T(t, s) \{ [E_1 E_2] R_1 [E_1 E_2]^T \} \xi_2(t, s) ds \\
& + \int_{t-h}^t \xi_2^T(t, s) \{ [E_1 E_2] R_2 [E_1 E_2]^T \} \xi_2(t, s) ds, \\
V_3(x_t) = & \int_{t-h}^t (h-t+s) \xi_2^T(t, s) \{ [E_2 E_3] R_3 [E_2 E_3]^T \} \xi_2(t, s) ds \\
& + \int_{t-h}^t (h-t+s)^2 \xi_2^T(t, s) \{ E_3 Q_1 E_3^T \} \xi_2(t, s) ds \\
& + \int_{t-h}^t (h-t+s)^3 \xi_2^T(t, s) \{ E_3 Q_2 E_3^T \} \xi_2(t, s) ds,
\end{aligned} \tag{18}$$

$$\begin{aligned}
V_4(x_t) = & \int_{t-h(t)}^t f^T(x(s)) S_1 f(x(s)) ds \\
& + \int_{t-h}^t f^T(x(s)) S_2 f(x(s)) ds \\
& + \int_{t-h(t)}^t \dot{x}^T(s) S_3 \dot{x}(s) ds \\
& + \int_{t-h}^t \dot{x}^T(s) S_4 \dot{x}(s) ds, \\
V_5(x_t) = & \int_{t-h}^t (h-t+s) \dot{x}^T(s) S_5 \dot{x}(s) ds \\
& + \int_{-h}^0 \int_{\theta}^0 \int_{t+\lambda}^t \dot{x}^T(s) S_6 \dot{x}(s) ds d\lambda d\theta, \\
V_6(x_t) = & \int_{t-r}^t (r-t+s) f^T(x(s)) S_7 f(x(s)) ds \\
& + \int_{-r}^0 \int_{\theta}^0 \int_{t+\lambda}^t f^T(x(s)) S_8 f(x(s)) ds d\lambda d\theta \\
& + 2 \sum_{i=1}^l \int_{-\rho_i r}^{-\rho_i-1 r} \int_{t+\theta}^t f(x(s)) Z_i f(x(s)) ds d\theta, \\
V_7(x_t) = & 2 \sum_{i=1}^n g_{1i} \int_0^{x_i(t)} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{1i} \int_0^{x_i(t)} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{1i} \int_0^{x_i(t)} (f_i(s) + \delta_i s) ds \\
& + 2 \sum_{i=1}^n g_{2i} \int_0^{x_i(t-h(t))} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{2i} \int_0^{x_i(t-h(t))} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{2i} \int_0^{x_i(t-h(t))} (f_i(s) + \delta_i s) ds \\
& + 2 \sum_{i=1}^n g_{3i} \int_0^{x_i(t-h)} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{3i} \int_0^{x_i(t-h)} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{3i} \int_0^{x_i(t-h)} (f_i(s) + \delta_i s) ds,
\end{aligned} \tag{19}$$

$$\begin{aligned}
V_4(x_t) = & \int_{t-h(t)}^t f^T(x(s)) S_1 f(x(s)) ds \\
& + \int_{t-h}^t f^T(x(s)) S_2 f(x(s)) ds \\
& + \int_{t-h(t)}^t \dot{x}^T(s) S_3 \dot{x}(s) ds \\
& + \int_{t-h}^t \dot{x}^T(s) S_4 \dot{x}(s) ds,
\end{aligned} \tag{20}$$

$$\begin{aligned}
V_5(x_t) = & \int_{t-h}^t (h-t+s) \dot{x}^T(s) S_5 \dot{x}(s) ds \\
& + \int_{-h}^0 \int_{\theta}^0 \int_{t+\lambda}^t \dot{x}^T(s) S_6 \dot{x}(s) ds d\lambda d\theta,
\end{aligned} \tag{21}$$

$$\begin{aligned}
V_6(x_t) = & \int_{t-r}^t (r-t+s) f^T(x(s)) S_7 f(x(s)) ds \\
& + \int_{-r}^0 \int_{\theta}^0 \int_{t+\lambda}^t f^T(x(s)) S_8 f(x(s)) ds d\lambda d\theta \\
& + 2 \sum_{i=1}^l \int_{-\rho_i r}^{-\rho_i-1 r} \int_{t+\theta}^t f(x(s)) Z_i f(x(s)) ds d\theta,
\end{aligned} \tag{22}$$

$$\begin{aligned}
V_7(x_t) = & 2 \sum_{i=1}^n g_{1i} \int_0^{x_i(t)} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{1i} \int_0^{x_i(t)} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{1i} \int_0^{x_i(t)} (f_i(s) + \delta_i s) ds \\
& + 2 \sum_{i=1}^n g_{2i} \int_0^{x_i(t-h(t))} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{2i} \int_0^{x_i(t-h(t))} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{2i} \int_0^{x_i(t-h(t))} (f_i(s) + \delta_i s) ds \\
& + 2 \sum_{i=1}^n g_{3i} \int_0^{x_i(t-h)} (f_i(s) - \delta_i^- s) ds \\
& + 2 \sum_{i=1}^n k_{3i} \int_0^{x_i(t-h)} (\delta_i^+ s - f_i(s)) ds \\
& + 2 \sum_{i=1}^n l_{3i} \int_0^{x_i(t-h)} (f_i(s) + \delta_i s) ds,
\end{aligned} \tag{23}$$

with

$$\begin{aligned}
 \xi_1^T(t) &= \left[x^T(t) \int_{t-h}^t x^T(s) ds \right], \\
 \xi_2^T(t, s) &= \left[x^T(t) \quad x^T(s) \quad \dot{x}^T(s) \right], \\
 \xi_3^T(t) &= \left[x^T(t) \quad \dot{x}^T(t) \quad x^T(t-h(t)) \quad x^T(t-h) \right. \\
 &\quad \left. \dot{x}^T(t-h(t)) \quad \dot{x}^T(t-h) \right], \\
 \xi_4^T(t) &= \left[\int_{t-h}^{t-h(t)} x^T(s) ds \quad \int_{t-h(t)}^t x^T(s) ds \quad f^T(x(t)) \right. \\
 &\quad \left. f^T(x(t-h(t))) \quad f^T(x(t-h)) \right], \\
 \xi_5^T(t) &= \left[\int_{t-\rho_1 r}^t f^T(x(s)) ds \cdots \int_{t-r}^{t-\rho_{l-1} r} f^T(x(s)) ds \right], \\
 \xi^T(t) &= \left[\xi_3^T(t) \quad \xi_4^T(t) \quad \xi_5^T(t) \quad \int_{-r}^0 \int_{t+\theta}^t f^T(x(s)) ds d\theta \right], \\
 E_i &= [0_{n \times (i-1)} \quad I_{n \times n} \quad 0_{n \times (3-i)}]^T \quad (i = 1, 2, 3).
 \end{aligned} \tag{24}$$

The time derivative of $V(x_t)$ along the trajectory of system (5) is given as

$$\begin{aligned}
 \dot{V}(x_t) &= \dot{V}_1(x_t) + \dot{V}_2(x_t) + \dot{V}_3(x_t) + \dot{V}_4(x_t) \\
 &\quad + \dot{V}_5(x_t) + \dot{V}_6(x_t) + \dot{V}_7(x_t),
 \end{aligned} \tag{25}$$

where

$$\begin{aligned}
 \dot{V}_1(x_t) &= 2\dot{\xi}_1^T(t) P \dot{\xi}_1(t) \\
 &= 2\dot{\xi}^T(t) [e_1 \quad e_7 + e_8] P [e_2 \quad e_1 - e_4]^T \xi(t), \\
 \dot{V}_2(x_t) &\leq \left[x^T(t) \quad x^T(t) \right] R_1 \left[x^T(t) \quad x^T(t) \right]^T \\
 &\quad + 2 \left[\dot{x}^T(t) \quad 0 \right] R_1 \int_{t-h(t)}^t \left[x^T(t) \quad x^T(s) \right]^T d(s) \\
 &\quad - (1 - h_D) \times \left[x^T(t) \quad x^T(t-h(t)) \right] R_1 \\
 &\quad \times \left[x^T(t) \quad x^T(t-h(t)) \right]^T + \left[x^T(t) \quad x^T(t) \right] R_2 \\
 &\quad \times \left[x^T(t) \quad x^T(t) \right]^T + 2 \left[\dot{x}^T(t) \quad 0 \right] R_2 \\
 &\quad \times \int_{t-h}^t \left[x^T(t) \quad x^T(s) \right]^T d(s) - \left[x^T(t) \quad x^T(t-h) \right] \\
 &\quad \times R_2 \left[x^T(t) \quad x^T(t-h) \right]^T
 \end{aligned}$$

$$\begin{aligned}
 &= \xi^T(t) \left\{ (e_1 \quad e_1) R_1 (e_1 \quad e_1)^T + 2(e_2 \quad 0) \right. \\
 &\quad \times R_1 (h(t) e_1 \quad e_8)^T - (1 - h_D) \\
 &\quad \times (e_1 \quad e_3) R_1 (e_1 \quad e_3)^T + (e_1 \quad e_1) \\
 &\quad \times R_2 (e_1 \quad e_1)^T + 2(e_2 \quad 0) R_2 \\
 &\quad \times (h e_1 \quad e_7 + e_8)^T - (e_1 \quad e_4) \\
 &\quad \left. \times R_2 (e_1 \quad e_4)^T \right\} \xi(t),
 \end{aligned}$$

$$\begin{aligned}
 \dot{V}_3(x_t) &= h \xi_2^T(t, t) \left\{ [E_2 E_3] R_3 [E_2 E_3]^T \right\} \xi_2(t, t) \\
 &\quad + \dot{x}^T(t) (h^2 Q_1 + h^3 Q_2) \dot{x}(t) + V_a(x(t)) \\
 &= \xi^T(t) \left\{ h(e_1 \quad e_2) R_3 (e_1 \quad e_2)^T \right. \\
 &\quad \left. + e_2 (h^2 Q_1 + h^3 Q_2) e_2^T \right\} \xi(t) \\
 &\quad + V_a(x(t)).
 \end{aligned} \tag{26}$$

Here, $V_a(x(t))$ is the sum of all integral terms expressed as

$$\begin{aligned}
 V_a(x(t)) &= - \int_{t-h}^t \eta_2(t, s) \left\{ [E_2 E_3] R_3 [E_2 E_3]^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h}^t 2(h-t+s) \eta_2(t, s) \left\{ E_3 Q_1 E_3^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h}^t 3(h-t+s)^2 \eta_2(t, s) \left\{ E_3 Q_2 E_3^T \right\} \eta_2(t, s) ds \\
 &\leq - \int_{t-h}^{t-h(t)} \eta_2(t, s) \left\{ [E_2 E_3] R_3 [E_2 E_3]^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h}^{t-h(t)} 2(h-t+s) \eta_2(t, s) \left\{ E_3 Q_1 E_3^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h}^{t-h(t)} 3(h-t+s)^2 \eta_2(t, s) \left\{ E_3 Q_2 E_3^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h(t)}^t \eta_2(t, s) \left\{ [E_2 E_3] R_3 [E_2 E_3]^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h(t)}^t 2(h(t)-t+s) \eta_2(t, s) \left\{ E_3 Q_1 E_3^T \right\} \eta_2(t, s) ds \\
 &\quad - \int_{t-h(t)}^t 3(h(t)-t+s)^2 \eta_2(t, s) \left\{ E_3 Q_2 E_3^T \right\} \\
 &\quad \times \eta_2(t, s) ds \\
 &= \widehat{V}_a(x(t)).
 \end{aligned} \tag{27}$$

Apply Lemma 2 to $\widehat{V}_a(x(t))$,

$$\begin{aligned} \widehat{V}_a(x(t)) &\leq \xi^T(t) \left\{ (h-h(t)) F_1^T R_3^{-1} F_1 + 2F_1^T [e_7 \ e_3 - e_4]^T \right. \\ &\quad + (h-h(t))^2 F_2^T Q_1^{-1} F_2 \\ &\quad + 4F_2^T [(h-h(t)) e_3 - e_7]^T \\ &\quad + 3(h-h(t)) F_3^T Q_1^{-1} F_3 \\ &\quad + 6F_3^T [(h-h(t)) e_3 - e_7]^T \\ &\quad + h(t) F_4^T R_3^{-1} F_4 + 2F_4^T (e_8 \ e_1 - e_3)^T \\ &\quad + h^2(t) F_5^T Q_1^{-1} F_5 + 4F_5^T [h(t) e_1 - e_8]^T \\ &\quad \left. + 3h(t) F_6^T Q_2^{-1} F_6 + 6F_6^T [h(t) e_1 - e_8]^T \right\} \\ &\quad \times \xi(t), \\ \dot{V}_4(x_t) &\leq f^T(x(t)) S_1 f(x(t)) \\ &\quad - (1-h_D) f^T(x(t-h(t))) S_1 f(x(t-h(t))) \\ &\quad + f^T(x(t)) S_2 f(x(t)) \\ &\quad - f^T(x(t-h)) S_2 f(x(t-h)) + \dot{x}^T(t) S_3 \dot{x}(t) \\ &\quad - (1-h_D) \dot{x}^T(t-h(t)) S_3 \dot{x}(t-h(t)) \\ &\quad + \dot{x}^T(t) S_4 \dot{x}(t) - \dot{x}^T(t-h) S_4 \dot{x}(t-h) \\ &= \xi^T(t) \left\{ e_9 (S_1 + S_2) e_9^T - (1-h_D) e_{10} S_1 e_{10}^T \right. \\ &\quad - e_{11} S_2 e_{11}^T + e_2 (S_3 + S_4) e_2^T \\ &\quad \left. - (1-h_D) e_5 S_3 e_5^T - e_6 S_4 e_6^T \right\} \xi(t), \end{aligned} \quad (28)$$

$$\begin{aligned} \dot{V}_5(x_t) &= \dot{x}^T(t) \left(h S_5 + \frac{h^2}{2} S_6 \right) \dot{x}(t) \\ &\quad - \int_{t-h}^t \dot{x}^T(s) S_5 \dot{x}(s) ds \\ &\quad - \int_{-h}^0 \int_{t+\theta}^t \dot{x}^T(s) S_6 \dot{x}(s) ds d\theta. \end{aligned} \quad (29)$$

From Lemmas 4 and 5, we have

$$\begin{aligned} & - \int_{t-h}^t \dot{x}^T(s) S_5 \dot{x}(s) ds \\ & \leq -\frac{2}{h} \left[\frac{1}{h} \int_{t-h}^t x(s) ds \right]^T \begin{bmatrix} S_5 & -S_5 \\ -S_5 & S_5 \end{bmatrix} \\ & \quad \times \left[\frac{1}{h} \int_{t-h}^t x(s) ds \right], \\ & - \int_{-h}^0 \int_{t+\theta}^t \dot{x}^T(s) S_6 \dot{x}(s) ds d\theta \\ & \leq \frac{2}{h^2} \left[\int_{t-h}^t h x(t) \right]^T \begin{bmatrix} -S_6 & S_6 \\ S_6 & -S_6 \end{bmatrix} \left[\int_{t-h}^t x(s) ds \right]. \end{aligned} \quad (30)$$

Then combining (29) and (30), we can obtain that

$$\begin{aligned} \dot{V}_5(x_t) &\leq \xi^T(t) \left\{ e_2 \left(h S_5 + \frac{h^2}{2} S_6 \right) e_2^T \right. \\ &\quad - 2e_1 S_6 e_1^T + \frac{4}{h} e_1 S_6 e_7^T + \frac{4}{h} e_1 S_6 e_8^T \\ &\quad + \frac{4}{h^2} e_4 S_5 e_7^T + \frac{4}{h^2} (t) e_4 S_5 e_8^T - \frac{2}{h} e_4 S_5 e_4^T \\ &\quad - e_7 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) e_7^T - e_7 \left(\frac{4}{h^3} S_5 + \frac{4}{h^2} S_6 \right) e_8^T \\ &\quad \left. - e_8 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) e_8^T \right\} \xi(t), \end{aligned} \quad (31)$$

$$\begin{aligned} \dot{V}_6(x_t) &= r f^T(x(t)) S_7 f(x(t)) \\ &\quad - \int_{t-r}^t f^T(x(s)) S_7 f(x(s)) ds + \frac{r^2}{2} f^T(x(t)) S_8 f(x(t)) \\ &\quad - \int_{-r}^0 \int_{t+\theta}^t f(x(s)) S_8 f(x(s)) ds d\theta \\ &\quad + \sum_{i=1}^l (\rho_i - \rho_{i-1}) r f^T(x(t)) Z_i f(x(t)) \\ &\quad - \sum_{i=1}^l \int_{t-\rho_i r}^{t-\rho_{i-1} r} f^T(x(s)) Z_i f(x(s)) ds. \end{aligned} \quad (32)$$

From Lemma 3, we get

$$\begin{aligned} & - \int_{t-r}^t f^T(x(s)) S_7 f^T(x(s)) ds \\ & \leq -\frac{1}{r} \int_{t-r}^t f^T(x(s)) ds S_7 \int_{t-r}^t f(x(s)) ds, \\ & - \int_{-r}^0 \int_{t+\theta}^t f^T(x(s)) S_8 f(x(s)) ds d\theta \\ & \leq -\frac{2}{r^2} \int_{-r}^0 \int_{t+\theta}^t f^T(x(s)) ds d\theta S_8 \\ & \quad \times \int_{-r}^0 \int_{t+\theta}^t f(x(s)) ds d\theta, \\ & - \int_{t-\rho_i r}^{t-\rho_{i-1} r} f^T(x(s)) Z_i f(x(s)) ds \\ & \leq -\frac{1}{(\rho_i - \rho_{i-1}) r} \int_{t-\rho_i r}^{t-\rho_{i-1} r} f^T(x(s)) ds Z_i \\ & \quad \times \int_{t-\rho_i r}^{t-\rho_{i-1} r} f(x(s)) ds. \end{aligned} \quad (33)$$

Then combining (32) and (33) we can have that

$$\begin{aligned}
 \dot{V}_6(x_t) &\leq r f^T(x(t)) S_7 f(x(t)) + \frac{r^2}{2} f^T(x(t)) S_8 f(x(t)) \\
 &\quad + \sum_{i=1}^l (\rho_i - \rho_{i-1}) r f^T(x(t)) Z_i f(x(t)) \\
 &\quad - \frac{1}{r} \sum_{i=1}^l \int_{t-\rho_i r}^{t-\rho_{i-1} r} f^T(x(s)) ds S_7 \sum_{i=1}^l \int_{t-\rho_i r}^{t-\rho_{i-1} r} f(x(s)) ds \\
 &\quad - \frac{2}{r^2} \int_{-r}^0 \int_{t+\theta}^t f^T(x(s)) ds d\theta S_8 \int_{-r}^0 \int_{t+\theta}^t f(x(s)) ds \\
 &\quad - \sum_{i=1}^l \frac{1}{(\rho_i - \rho_{i-1}) r} \int_{t-\rho_i r}^{t-\rho_{i-1} r} f^T(x(s)) ds Z_i \\
 &\quad \times \int_{t-\rho_i r}^{t-\rho_{i-1} r} f(x(s)) ds \\
 &= \xi^T(t) \left\{ e_9 \left(r S_7 + \frac{r^2}{2} S_8 + \sum_{i=1}^l (\rho_i - \rho_{i-1}) r Z_i \right) e_9^T \right. \\
 &\quad \left. - \frac{2}{r^2} e_{12+l} S_8 e_{12+l}^T - \sum_{i=1}^l \frac{1}{(\rho_i - \rho_{i-1}) r} e_{11+i} \right. \\
 &\quad \times Z_i e_{11+i}^T - \frac{1}{r} (e_{12} + \dots + e_{11+l}) \\
 &\quad \left. \times S_7 (e_{12} + \dots + e_{11+l})^T \right\} \xi(t), \tag{34}
 \end{aligned}$$

$$\begin{aligned}
 \dot{V}_7(x_t) &\leq 2 \left[f^T(x(t)) (G_1 - K_1 + L_1) \right. \\
 &\quad \left. + x^T(t) (\bar{\Sigma} K_1 - \underline{\Sigma} G_1 + L_1 \Sigma) \right] \\
 &\quad \times \dot{x}(t) + 2(1 - h_D) \\
 &\quad \times \left[f^T(x(t-h(t))) (G_2 - K_2 + L_2) \right. \\
 &\quad \left. + x^T(t-h(t)) (\bar{\Sigma} K_2 - \underline{\Sigma} G_2 + L_2 \Sigma) \right] \\
 &\quad \times \dot{x}(t-h(t)) \\
 &\quad + 2 \left[f^T(x(t-h)) (G_3 - K_3 + L_3) \right. \\
 &\quad \left. + x^T(t-h) (\bar{\Sigma} K_3 - \underline{\Sigma} G_3 + L_3 \Sigma) \right] \\
 &\quad \times \dot{x}(t-h) \\
 &= 2 \xi^T(t) \left\{ e_1 (\bar{\Sigma} K_1 - \underline{\Sigma} G_1 + L_1 \Sigma) e_2^T \right. \\
 &\quad + 2e_2 (G_1 - K_1 + L_1) e_9^T \\
 &\quad + 2e_3 (\bar{\Sigma} K_2 - \underline{\Sigma} G_2 + L_2 \Sigma) e_5^T \\
 &\quad \left. + 2e_5 (G_2 - K_2 + L_2) e_{10}^T \right\} \xi(t)
 \end{aligned}$$

$$\begin{aligned}
 &+ 2e_4 (\bar{\Sigma} K_3 - \underline{\Sigma} G_3 + L_3 \Sigma) e_6^T \\
 &+ 2e_6 (G_3 - K_3 + L_3) e_{11}^T \} \xi(t). \tag{35}
 \end{aligned}$$

From (6), for any positive diagonal matrices $M_i = \text{diag}\{m_{i1}, \dots, \min\}$ ($i = 1, 2, 3, 4$) one can easily check

$$\begin{aligned}
 0 &\leq \left[x^T(t) \Sigma M_1 \Sigma x(t) - f^T(x(t)) M_1 f(x(t)) \right] \\
 &\quad + \left[-x^T(t) M_2 \Sigma_1 x(t) + 2x^T(t) M_2 \Sigma_2 f(x(t)) \right. \\
 &\quad \left. - f^T(x(t)) M_2 f(x(t)) \right] \\
 &\quad + \left[-x^T(t-h(t)) M_3 \right. \\
 &\quad \times \Sigma_1 x(t-h(t)) + 2x^T(t-h(t)) \\
 &\quad \times M_3 \Sigma_2 f(x(t-h(t))) - f^T(x(t-h(t))) \\
 &\quad \times M_3 f(x(t-h(t))) \left. \right] \\
 &\quad + \left[-x^T(t-h) M_4 \Sigma_1 x(t-h) + 2x^T(t-h) M_4 \Sigma_2 f \right. \\
 &\quad \times (x(t-h)) - f^T(x(t-h)) M_4 f(x(t-h)) \left. \right] \\
 &= \xi^T(t) \left\{ e_1 (\Sigma M_1 \Sigma - M_2 \Sigma_1) e_1^T + 2e_1 M_2 \Sigma_2 e_9^T - e_3 M_3 \Sigma_1 e_3^T \right. \\
 &\quad + 2e_3 M_3 \Sigma_2 e_{10}^T - e_9 (M_1 + M_2) e_9^T \\
 &\quad - e_{10} M_3 e_{10}^T - e_4 M_4 \Sigma_1 e_4^T + 2e_4 M_4 \Sigma_2 e_{11}^T \\
 &\quad \left. - e_{11} M_4 e_{11}^T \right\} \xi(t). \tag{36}
 \end{aligned}$$

Furthermore, for arbitrary matrices T_1, T_2, T_3, T_4, T_5 with appropriate dimensions, we have

$$\begin{aligned}
 &2\dot{x}^T(t) T_1 \\
 &\quad \times \left[-\dot{x}(t) - W_0 x(t) + W_1 f(x(t)) \right. \\
 &\quad \left. + W_2 f(x(t-h(t))) \right. \\
 &\quad \left. + W_3 \int_{t-r}^t f^T(x(s)) ds + W_4 (\dot{x}(t-h(t))) \right] \\
 &= \xi^T(t) \left\{ e_2 (-T_1 - T_1^T) e_2^T - 2e_1 W_0^T T_1^T e_2^T \right. \\
 &\quad + 2e_2 T_1 W_1 e_9^T + 2e_2 T_1 W_2 e_{10}^T \\
 &\quad + 2e_2 T_1 W_3 (e_{12} + \dots + e_{11+l})^T \\
 &\quad \left. + 2e_2 T_1 W_4 e_5^T \right\} \xi(t) = 0, \tag{37}
 \end{aligned}$$

$$\begin{aligned}
& 2x^T(t)T_2 \\
& \times \left[-\dot{x}(t) - W_0x(t) + W_1f(x(t)) + W_2f(x(t-h(t))) \right. \\
& \quad \left. + W_3 \int_{t-r}^t f^T(x(s))ds + W_4(\dot{x}(t-h(t))) \right] \\
& = \xi^T(t) \left\{ -2e_1T_2e_2^T + e_1(-T_2W_0 - W_0^TT_2^T)e_1^T \right. \\
& \quad + 2e_1T_2W_1e_9^T + 2e_1T_2W_2e_{10}^T \\
& \quad + 2e_1T_2W_3(e_{12} + \dots + e_{11+l})^T \\
& \quad \left. + 2e_2T_2W_4e_5^T \right\} \xi(t) = 0,
\end{aligned} \tag{38}$$

$$\begin{aligned}
& 2f^T(x(t))T_3 \\
& \times \left[-\dot{x}(t) - W_0x(t) + W_1f(x(t)) \right. \\
& \quad + W_2f(x(t-h(t))) + W_3 \int_{t-r}^t f^T(x(s))ds \\
& \quad \left. + W_4(\dot{x}(t-h(t))) \right] \\
& = \xi^T(t) \left\{ -2e_2T_3^Te_9^T - 2e_1W_0^TT_3^Te_9^T \right. \\
& \quad + e_9(T_3W_1 + W_1^TT_3^T)e_9^T + 2e_9T_3W_2e_{10}^T \\
& \quad + 2e_9T_3W_3(e_{12} + \dots + e_{11+l})^T \\
& \quad \left. + 2e_5W_4^TT_3^Te_9^T \right\} \xi(t) = 0,
\end{aligned} \tag{39}$$

$$\begin{aligned}
& 2f^T(x(t-h(t)))T_4 \\
& \times \left[-\dot{x}(t) - W_0x(t) + W_1f(x(t)) \right. \\
& \quad + W_2f(x(t-h(t))) \\
& \quad + W_3 \int_{t-r}^t f^T(x(s))ds \\
& \quad \left. + W_4(\dot{x}(t-h(t))) \right] \\
& = \xi^T(t) \left\{ -2e_2T_4^Te_{10}^T - 2e_1W_0^TT_4^Te_{10}^T \right. \\
& \quad + e_9W_1^TT_4^Te_{10}^T + e_{10}(T_4W_2 + W_2^TT_4^T)e_{10}^T \\
& \quad + 2e_{10}T_4W_3(e_{12} + \dots + e_{11+l})^T \\
& \quad \left. + 2e_5W_4^TT_4^Te_{10}^T \right\} \xi(t) = 0,
\end{aligned} \tag{40}$$

$$\begin{aligned}
& \dot{x}^T(t-h(t))T_5 \\
& \times \left[-\dot{x}(t) - W_0x(t) + W_1f(x(t)) \right. \\
& \quad + W_2f(x(t-h(t))) \\
& \quad + W_3 \int_{t-r}^t f^T(x(s))ds \\
& \quad \left. + W_4(\dot{x}(t-h(t))) \right]
\end{aligned}$$

$$\begin{aligned}
& = \xi^T(t) \left\{ -2e_2T_5^Te_5^T - 2e_1W_0^TT_5^Te_5^T \right. \\
& \quad + e_5T_5W_1e_9^T + e_5T_5W_2e_{10}^T \\
& \quad + 2e_5T_5W_3(e_{12} + \dots + e_{11+l})^T \\
& \quad \left. + 2e_5(T_5W_4 + W_4^TT_5^T)e_5^T \right\} \xi(t) = 0.
\end{aligned} \tag{41}$$

The combination of (26)–(37) gives that

$$V(x_t) \leq \xi^T(t) \{ \Pi_0 + h(t) \Pi_1 + \Pi_h \} \xi(t), \tag{42}$$

where Π_0, Π_1 are defined in (13) and (14), respectively, and

$$\begin{aligned}
\Pi_h &= (h-h(t))F_1^TR_3^{-1}F_1 \\
&+ (h-h(t))^2F_2^TQ_1^{-1}F_2 + 3(h-h(t))F_3^TQ_1^{-1}F_3 \\
&+ h(t)F_4^TR_3^{-1}F_4 + h^2(t)F_5^TQ_1^{-1}F_5 + 3h(t)F_6^TQ_2^{-1}F_6.
\end{aligned} \tag{43}$$

Note that the scalar valued function $\xi^T(t)\{\Pi_0 + h(t)\Pi_1 + \Pi_h\}\xi(t)$ is quadratic function on the scalar $h(t)$ and the coefficient of second order is $\xi^T(t)[F_2^TQ_1^{-1}F_2 + F_5^TQ_1^{-1}F_5]\xi(t) \geq 0$ since $Q_1 > 0$. This means that the function $\xi^T(t)\{\Pi_0 + h(t)\Pi_1 + \Pi_h\}\xi(t)$ is a convex quadratic function for $h(t)$. Finally, apply Fact 1 and Lemma 1 in order, then we get

$$\Xi_1 < 0 \text{ in (22)}, \quad \Xi_2 < 0 \text{ in (23)} \tag{44}$$

$$\begin{aligned}
& \iff [\Pi_0 + h(t)\Pi_1 + \Pi_h]_{h(t)=0} < 0, \\
& [\Pi_0 + h(t)\Pi_1 + \Pi_h]_{h(t)=h} < 0,
\end{aligned} \tag{45}$$

$$\iff \Pi_0 + h(t)\Pi_1 + \Pi_h < 0, \quad \forall h(t) \in [0, h], \tag{46}$$

which means the asymptotic stability of the system (19). This completes the proof. $\square$

Remark 7. In Theorem 6, the augmented vector $\xi(t)$ has integrating terms of activation function $f(x(t))$ which are $\int_{t-\rho_1r}^t f^T(x(s))ds, \dots, \int_{t-r}^{t-\rho_{l-1}r} f^T(x(s))ds$ and $\int_{-r}^0 \int_{t+\theta}^t f^T(x(s))dsd\theta$. By these terms, more past history of $f(x(t))$ can be used, which lead to less conservative results.

Remark 8. Compared with those in previous articles, Ours constructed a new type of Lyapunov-Krasovskii functional which has three differences: (1) an independent augmented variable $\int_{t-h}^t x^T(s)ds$; (2) the cross terms between entries in $\xi_1(t), \xi_2(t, s)$, respectively; (3) quadratic terms multiplied by first, second, and third degrees of a scalar function $h-t+s$ by 1 means the number increase of the integral by 1.

Remark 9. Compared with traditional approach to deal with term like $\int_{t-h}^t \dot{x}^T(s)S_5\dot{x}(s)ds$, Lemma 5 provides a new handling method. This new handling method can establish the relationship among $\int_{t-h(t)}^t x^T(s)ds, \int_{t-h}^{t-h(t)} x^T(s)ds$ and $x(t-h)$, which may significantly reduce the conservatism of stability criteria.

Remark 10. When $W_3 = 0$, the system (5) reduces to

$$\begin{aligned} \dot{x}(t) = & -W_0 x(t) + W_1 f(x(t)) \\ & + W_2 f(x(t-h(t))) + W_4 \dot{x}(t-h(t)). \end{aligned} \quad (47)$$

Similarly, based on Theorem 6, we can obtain the asymptotic stability for system (47) as follows.

Theorem 11. For given scalars $h > 0$ and $h_D < 1$, the system (47) with the neuron activation function $f(x(t))$ satisfying the condition (6) is asymptotically stable if there exists $P > 0$, $R_i^T = R_i > 0$ ($i = 1, 2, 3$), $Q_i^T = Q_i > 0$ ($i = 1, 2$), $S_i^T = S_i > 0$ ($i = 1, \dots, 6$), diagonal matrices $G_i = \text{diag}\{g_{i1}, g_{i2}, \dots, g_{in}\} > 0$, $K_i = \text{diag}\{k_{i1}, k_{i2}, \dots, k_{in}\} > 0$, $L_i = \text{diag}\{l_{i1}, l_{i2}, \dots, l_{in}\} > 0$, ($i = 1, 2, 3$), and $M = \text{diag}\{m_{i1}, m_{i2}, \dots, m_{in}\} > 0$, ($i = 1, 2, 3, 4$), T_i ($i = 1, \dots, 5$) and F_i ($i = 1, \dots, 6$) with appropriate dimensions such that the following symmetric linear matrix inequality holds:

$$\hat{\Pi}_1 = \begin{bmatrix} \hat{\Pi}_0 & hF_1^T & hF_2^T & hF_3^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (48)$$

$$\hat{\Pi}_2 = \begin{bmatrix} \hat{\Pi}_0 + h\hat{\Pi}_1 & hF_4^T & hF_5^T & hF_6^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (49)$$

where

$$\begin{aligned} \hat{\Pi}_0 = & \left\langle 2[\hat{e}_1 \ \hat{e}_7 + \hat{e}_8] P[e_2 \ \hat{e}_1 - e_4]^T \right. \\ & + 2[\hat{e}_2 \ 0] R_1[0 \ \hat{e}_8]^T \\ & + 2[\hat{e}_2 \ 0] R_2[h\hat{e}_1 \ \hat{e}_7 + \hat{e}_8]^T \Big\rangle_s + [\hat{e}_1 \ \hat{e}_1] \\ & \times (R_1 + R_2)[\hat{e}_1 \ \hat{e}_1]^T - (1 - h_D)[\hat{e}_1 \ \hat{e}_3] \\ & \times R_1[\hat{e}_1 \ \hat{e}_3]^T - [\hat{e}_1 \ \hat{e}_4] R_2[\hat{e}_1 \ \hat{e}_4]^T + h[\hat{e}_1 \ \hat{e}_2] R_3 \\ & \times [\hat{e}_1 \ \hat{e}_2]^T + \hat{e}_2(h^2 Q_1 + h^3 Q_2)e_2^T \\ & + \left\langle 2F_1^T[\hat{e}_7 \ \hat{e}_3 - \hat{e}_4]^T + 4F_2^T[h\hat{e}_3 - \hat{e}_7]^T \right. \\ & + 6F_3^T[h\hat{e}_3 - \hat{e}_7]^T + 2F_4^T[\hat{e}_8 \ \hat{e}_1 - \hat{e}_3]^T - 4F_5^T \hat{e}_8^T \\ & \left. - 6F_6^T \hat{e}_8^T \right\rangle_s + \hat{e}_9(S_1 + S_2)\hat{e}_9^T - (1 - h_D)\hat{e}_{10}S_1\hat{e}_{10}^T \\ & - \hat{e}_{11}S_2\hat{e}_{11}^T - \hat{e}_6S_4\hat{e}_6^T + \hat{e}_2(S_3 + S_4)\hat{e}_2^T \\ & - (1 - h_D)\hat{e}_5S_3\hat{e}_5^T + \hat{e}_2\left(hS_5 + \frac{h^2}{2}S_6\right)\hat{e}_2^T \end{aligned}$$

$$\begin{aligned} & - 2\hat{e}_1S_6\hat{e}_1^T + \frac{4}{h}\hat{e}_1S_6\hat{e}_7^T + \frac{4}{h^2}\hat{e}_4S_5\hat{e}_7^T + \frac{4}{h^2}\hat{e}_4S_5\hat{e}_8^T \\ & - \hat{e}_7\left(\frac{2}{h^3}S_5 + \frac{2}{h^2}S_6\right)\hat{e}_7^T - \hat{e}_7\left(\frac{4}{h^3}S_5 + \frac{4}{h^2}S_6\right)\hat{e}_8^T \\ & - \hat{e}_8\left(\frac{2}{h^3}S_5 + \frac{2}{h^2}S_6\right)\hat{e}_8^T + \hat{e}_1(\bar{\Sigma}K_1 - \underline{\Sigma}G_1 + L_1\Sigma)\hat{e}_2^T \\ & + 2\hat{e}_2(G_1 - K_1 + L_1)\hat{e}_9^T + 2\hat{e}_3(\bar{\Sigma}K_2 - \underline{\Sigma}G_2 + L_2\Sigma) \\ & \times \hat{e}_5^T + 2\hat{e}_5(G_2 - K_2 + L_2)\hat{e}_{10}^T \\ & + 2\hat{e}_4(\bar{\Sigma}K_3 - \underline{\Sigma}G_3 + L_3\Sigma)\hat{e}_6^T + 2\hat{e}_6(G_3 - K_3 + L_3) \\ & \times \hat{e}_{11}^T + e_1(\Sigma M_1\Sigma - M_2\Sigma_1)\hat{e}_1^T + 2\hat{e}_1M_2\Sigma_2\hat{e}_9^T \\ & - \hat{e}_3M_3\Sigma_1\hat{e}_3^T + 2\hat{e}_3M_3\Sigma_2\hat{e}_{10}^T - \hat{e}_9(M_1 + M_2)\hat{e}_9^T \\ & - \hat{e}_{10}M_3\hat{e}_{10}^T - \hat{e}_4M_4\Sigma_1\hat{e}_4^T + 2\hat{e}_4M_4\Sigma_2\hat{e}_{11}^T \\ & + \hat{e}_2(-T_1 - T_1^T)\hat{e}_2^T - \hat{e}_{11}M_4\hat{e}_{11}^T - 2\hat{e}_1W_0^T T_1^T \hat{e}_2^T \\ & + 2\hat{e}_2T_1W_1\hat{e}_9^T + 2\hat{e}_2T_1W_2\hat{e}_{10}^T - 2e_1T_2\hat{e}_2^T \\ & + \hat{e}_1(-T_2W_0 - W_0^T T_2^T)\hat{e}_1^T + 2\hat{e}_1T_2W_1\hat{e}_9^T \\ & + 2\hat{e}_1T_2W_2\hat{e}_{10}^T + 2\hat{e}_2T_2W_4\hat{e}_5^T - 2\hat{e}_1W_0^T T_3^T \hat{e}_9^T \\ & + 2\hat{e}_9T_3W_2\hat{e}_{10}^T + \hat{e}_9(T_3W_1 + W_1^T T_3^T)\hat{e}_9^T \\ & + 2\hat{e}_5W_4^T T_3^T \hat{e}_9^T - 2\hat{e}_2T_4^T \hat{e}_{10}^T - 2\hat{e}_1W_0^T T_4^T \hat{e}_{10}^T \\ & + \hat{e}_9W_1^T T_4^T \hat{e}_{10}^T + \hat{e}_{10}(T_4W_2 + W_2^T T_4^T)\hat{e}_{10}^T \\ & + 2\hat{e}_5W_4^T T_3^T \hat{e}_9^T - 2\hat{e}_2T_5^T \hat{e}_5^T - 2\hat{e}_1W_0^T T_5^T \hat{e}_5^T \\ & + \hat{e}_5T_5W_1\hat{e}_9^T + \hat{e}_5T_5W_2\hat{e}_{10}^T - \frac{2}{h}\hat{e}_4S_5\hat{e}_4^T \\ & + \frac{4}{h}\hat{e}_1S_6\hat{e}_8^T + 2\hat{e}_5(T_5W_4 + W_4^T T_5^T)\hat{e}_5^T \\ & + 2\hat{e}_5W_4^T T_4^T \hat{e}_{10}^T + 2\hat{e}_2T_1W_4\hat{e}_5^T - 2\hat{e}_2T_3^T \hat{e}_9^T, \end{aligned}$$

$$\begin{aligned} \hat{\Pi}_1 = & \left\langle 2(\hat{e}_2 \ 0) R_1(\hat{e}_1 \ 0)^T - 4F_2^T \hat{e}_3^T \right. \\ & \left. - 6F_3^T \hat{e}_3^T + 4F_5^T \hat{e}_1^T + 6F_6^T \hat{e}_1^T \right\rangle_s, \end{aligned} \quad (50)$$

with

$$\langle \cdot \rangle_s = \frac{1}{2}[(\cdot) + (\cdot)^T], \quad (51)$$

$$\hat{e}_i = [0_{n \times (i-1)} \ I_{n \times n} \ 0_{n \times (11-i)}]^T \quad (i = 1, \dots, 11).$$

Remark 12. When $W_4 = 0$, the system (5) reduces to

$$\begin{aligned} \dot{x}(t) = & -W_0 x(t) + W_1 f(x(t)) \\ & + W_2 f(x(t-h(t))) + W_3 \int_{t-r}^t f^T(x(s)) ds. \end{aligned} \quad (52)$$

Similarly, based on Theorem 6, we can obtain the asymptotical stability for system (52) as follows.

Theorem 13. For given scalars $h > 0$ and $h_D < 1$, the system (52) with the neuron activation function $f(x(t))$ satisfying the condition (6) is asymptotically stable if there exists $P > 0$, $R_i^T = R_i > 0$ ($i = 1, 2, 3$), $Q_i^T = Q_i > 0$ ($i = 1, 2$), $S_i^T = S_i > 0$ ($i = 1, 2, 5, \dots, 8$), $Z_i^T = Z_i > 0$ ($i = 1, \dots, l$), diagonal matrices $G_1 = \text{diag}\{g_1, g_2, \dots, g_n\} > 0$, $K_1 = \text{diag}\{k_1, k_2, \dots, k_n\} > 0$, $L_1 = \text{diag}\{l_1, l_2, \dots, l_n\} > 0$, and $M = \text{diag}\{m_{i1}, m_{i2}, \dots, m_{in}\} > 0$, ($i = 1, 2, 3, 4$), T_i ($i = 1, \dots, 4$) and F_i ($i = 1, \dots, 6$) with appropriate dimensions such that the following symmetric linear matrix inequality holds:

$$\tilde{\Xi}_1 = \begin{bmatrix} \tilde{\Pi}_0 & hF_1^T & hF_2^T & hF_3^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (53)$$

$$\tilde{\Xi}_2 = \begin{bmatrix} \tilde{\Pi}_0 + h\tilde{\Pi}_1 & hF_4^T & hF_5^T & hF_6^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (54)$$

where

$$\begin{aligned} \tilde{\Pi}_0 = & \left\langle 2 \begin{bmatrix} \tilde{e}_1 & \tilde{e}_5 + \tilde{e}_6 \end{bmatrix} P \begin{bmatrix} \tilde{e}_2 & \tilde{e}_1 - \tilde{e}_4 \end{bmatrix}^T \right. \\ & + 2 \begin{bmatrix} \tilde{e}_2 & 0 \end{bmatrix} R_1 \begin{bmatrix} 0 & \tilde{e}_6 \end{bmatrix}^T + 2 \begin{bmatrix} \tilde{e}_2 & 0 \end{bmatrix} \\ & \times R_2 \left[h\tilde{e}_1 \quad \tilde{e}_5 + \tilde{e}_6 \right]^T \Big\rangle_s + \begin{bmatrix} \tilde{e}_1 & \tilde{e}_1 \end{bmatrix} \\ & \times (R_1 + R_2) \begin{bmatrix} \tilde{e}_1 & \tilde{e}_1 \end{bmatrix}^T - (1 - h_D) \begin{bmatrix} \tilde{e}_1 & e_3 \end{bmatrix} \\ & \times R_1 \begin{bmatrix} \tilde{e}_1 & \tilde{e}_3 \end{bmatrix}^T - \begin{bmatrix} \tilde{e}_1 & e_4 \end{bmatrix} R_2 \begin{bmatrix} \tilde{e}_1 & \tilde{e}_4 \end{bmatrix}^T \\ & + h \begin{bmatrix} \tilde{e}_1 & \tilde{e}_2 \end{bmatrix} R_3 \times \begin{bmatrix} \tilde{e}_1 & \tilde{e}_2 \end{bmatrix}^T + \tilde{e}_2 \left(h^2 Q_1 + h^3 Q_2 \right) \\ & \times \tilde{e}_2^T + \left\langle 2F_1^T \begin{bmatrix} \tilde{e}_5 & \tilde{e}_3 - \tilde{e}_4 \end{bmatrix}^T + 4F_2^T \left[h\tilde{e}_3 - \tilde{e}_5 \right]^T \right. \\ & + 6F_3^T \left[h\tilde{e}_3 - \tilde{e}_5 \right]^T + 2F_4^T \begin{bmatrix} \tilde{e}_6 & \tilde{e}_1 - \tilde{e}_3 \end{bmatrix}^T \\ & \left. - 4F_5^T \tilde{e}_6^T - 6F_6^T \tilde{e}_6^T \right\rangle_s + \tilde{e}_7 (S_1 + S_2) \tilde{e}_7^T \\ & - (1 - h_D) \tilde{e}_8 S_1 \tilde{e}_8^T - \tilde{e}_9 S_2 \tilde{e}_9^T + \tilde{e}_2 \left(hS_5 + \frac{h^2}{2} S_6 \right) \\ & \times \tilde{e}_2^T - 2\tilde{e}_1 S_6 \tilde{e}_1^T + \frac{4}{h} \tilde{e}_1 S_6 \tilde{e}_5^T + \tilde{e}_7 W_1^T T_4^T \tilde{e}_8^T \\ & + \tilde{e}_8 (T_4 W_2 + W_2^T T_4^T) \tilde{e}_8^T + \frac{4}{h} \tilde{e}_1 \times S_6 \tilde{e}_6^T + \frac{4}{h^2} \tilde{e}_4 S_5 \tilde{e}_5^T \\ & + \frac{4}{h^2} \tilde{e}_4 S_5 \tilde{e}_6^T - \frac{2}{h} \tilde{e}_4 S_5 \tilde{e}_4^T - \tilde{e}_5 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) \tilde{e}_5^T \\ & - \tilde{e}_5 \left(\frac{4}{h^3} S_5 + \frac{4}{h^2} S_6 \right) \tilde{e}_6^T - \tilde{e}_6 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) \tilde{e}_6^T \end{aligned}$$

$$\begin{aligned} & + \tilde{e}_7 \left(rS_7 + \frac{r^2}{2} S_8 + \sum_{i=1}^l (\rho_i - \rho_{i-1}) rZ_i \right) \tilde{e}_7^T \\ & - \sum_{i=1}^l \frac{1}{(\rho_i - \rho_{i-1}) r} \tilde{e}_{9+i} Z_i \tilde{e}_{9+i}^T - \frac{1}{r} (\tilde{e}_{10} + \dots + \tilde{e}_{9+l}) \\ & \times S_7 (\tilde{e}_{10} + \dots + \tilde{e}_{9+l})^T - \frac{2}{r^2} \tilde{e}_{10+l} S_8 \tilde{e}_{10+l}^T \\ & + \tilde{e}_1 (\bar{\Sigma} K_1 - \bar{\Sigma} G_1 + L_1 \bar{\Sigma}) \tilde{e}_2^T + 2\tilde{e}_2 (G_1 - K_1 + L_1) \tilde{e}_7^T \\ & + \tilde{e}_1 (\Sigma M_1 \Sigma - M_2 \Sigma_1) \tilde{e}_1^T + 2e_1 M_2 \Sigma_2 \tilde{e}_7^T - e_3 M_3 \Sigma_1 \tilde{e}_3^T \\ & + 2e_7 T_3 W_2 \tilde{e}_8^T + 2\tilde{e}_3 M_3 \Sigma_2 \tilde{e}_8^T - \tilde{e}_7 (M_1 + M_2) \tilde{e}_7^T \\ & - \tilde{e}_8 M_3 \tilde{e}_8^T - \tilde{e}_4 M_4 \Sigma_1 \tilde{e}_4^T + 2\tilde{e}_4 M_4 \Sigma_2 \tilde{e}_9^T \\ & + \tilde{e}_2 (-T_1 - T_1^T) \tilde{e}_2^T - \tilde{e}_9 M_4 \tilde{e}_9^T - 2\tilde{e}_1 W_0^T T_1^T \tilde{e}_2^T \\ & + 2e_2 T_1 W_1 \tilde{e}_7^T + 2\tilde{e}_2 T_1 W_2 \tilde{e}_8^T + 2\tilde{e}_2 T_1 W_3 \\ & \times (\tilde{e}_{10} + \dots + \tilde{e}_{9+l})^T - 2\tilde{e}_1 \times W_0^T T_4^T \tilde{e}_8^T - 2\tilde{e}_1 T_2 \tilde{e}_2^T \\ & + \tilde{e}_1 (-T_2 W_0 - W_0^T T_2^T) \tilde{e}_1^T + 2\tilde{e}_1 T_2 W_1 \tilde{e}_7^T \\ & + 2\tilde{e}_1 T_2 W_2 \tilde{e}_8^T - 2\tilde{e}_2 T_4^T \tilde{e}_8^T + 2\tilde{e}_1 T_2 W_3 \\ & \times (\tilde{e}_{10} + \dots + \tilde{e}_{9+l})^T - 2\tilde{e}_2 T_3^T \tilde{e}_7^T - 2e_1 W_0^T T_3^T \tilde{e}_7^T \\ & + \tilde{e}_7 (T_3 W_1 + W_1^T T_3^T) \tilde{e}_7^T \\ & + 2\tilde{e}_7 T_3 W_3 (\tilde{e}_{10} + \dots + \tilde{e}_{9+l})^T \\ & + 2\tilde{e}_8 T_4 W_3 (\tilde{e}_{10} + \dots + \tilde{e}_{9+l})^T, \end{aligned}$$

$$\begin{aligned} \tilde{\Pi}_1 = & \left\langle 2 \begin{bmatrix} \tilde{e}_2 & 0 \end{bmatrix} R_1 \begin{bmatrix} \tilde{e}_1 & \tilde{e}_0 \end{bmatrix}^T - 4F_2^T \tilde{e}_3^T \right. \\ & \left. - 6F_3^T \tilde{e}_3^T + 4F_5^T \tilde{e}_1^T + 6F_6^T \tilde{e}_1^T \right\rangle_s, \end{aligned} \quad (55)$$

with

$$\langle \cdot \rangle_s = \frac{1}{2} [(\cdot) + (\cdot)^T], \quad (56)$$

$$\tilde{e}_i = [0_{n \times (i-1)} \quad I_{n \times n} \quad 0_{n \times (10+l-i)}]^T \quad (i = 1, \dots, 10 + l).$$

Remark 14. When $W_3 = 0$ and $W_4 = 0$, the system (5) reduces to

$$\dot{x}(t) = -W_0 x(t) + W_1 f(x(t)) + W_2 f(x(t - h(t))). \quad (57)$$

Similarly, based on Theorem 6, we can obtain the asymptotical stability for system (57) as follows.

Theorem 15. For given scalars $h > 0$ and $h_D < 1$, the system (57) with the neuron activation function $f(x(t))$ satisfying the condition (6) is asymptotically stable if there exists $P > 0$, $R_i^T = R_i > 0$ ($i = 1, 2, 3$), $Q_i^T = Q_i > 0$ ($i = 1, 2$), $S_i^T = S_i > 0$ ($i = 1, 2, 5, 6$), diagonal matrices $G_1 = \text{diag}\{g_{i1}, g_{i2}, \dots, g_{in}\} > 0$,

$K_1 = \text{diag}\{k_1, k_2, \dots, k_n\} > 0$, $L_1 = \text{diag}\{l_1, l_2, \dots, l_n\} > 0$, and $M = \text{diag}\{m_{i1}, m_{i2}, \dots, m_{in}\} > 0$, ($i = 1, 2, 3, 4$), T_i ($i = 1, \dots, 4$) and F_i ($i = 1, \dots, 6$) with appropriate dimensions such that the following symmetric linear matrix inequality holds:

$$\check{\Xi}_1 = \begin{bmatrix} \check{\Pi}_0 & hF_1^T & hF_2^T & hF_3^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (58)$$

$$\check{\Xi}_2 = \begin{bmatrix} \check{\Pi}_0 + h\check{\Pi}_1 & hF_4^T & hF_5^T & hF_6^T \\ * & -hR_3 & 0 & 0 \\ * & * & -Q_1 & 0 \\ * & * & * & -\frac{h}{3}Q_2 \end{bmatrix} < 0, \quad (59)$$

where

$$\begin{aligned} \check{\Pi}_0 = & \left\langle 2[\check{e}_1 \quad \check{e}_5 + \check{e}_6] P[e_2 \quad \check{e}_1 - e_4]^T + 2[\check{e}_2 \quad 0] R_1[0 \quad e_6]^T \right. \\ & + 2[\check{e}_2 \quad 0] R_2[h\check{e}_1 \quad \check{e}_5 + \check{e}_6]^T \Big\rangle_s + [\check{e}_1 \quad \hat{e}_1] \\ & \times (R_1 + R_2)[\check{e}_1 \quad \check{e}_1]^T - (1 - h_D)[\check{e}_1 \quad \check{e}_3] R_1[\check{e}_1 \quad \check{e}_3]^T \\ & - [\check{e}_1 \quad \check{e}_4] R_2[\check{e}_1 \quad \check{e}_4]^T + h[\check{e}_1 \quad \check{e}_2] R_3 \\ & \times [\check{e}_1 \quad \check{e}_2]^T + \check{e}_2(h^2 Q_1 + h^3 Q_2)e_2^T \\ & + \left\langle 2F_1^T[\check{e}_5 \quad \check{e}_3 - \check{e}_4]^T + 4F_2^T[h\check{e}_3 - \check{e}_5]^T \right. \\ & + 6F_3^T[h\check{e}_3 - \check{e}_5]^T + 2F_4^T[\check{e}_6 \quad \check{e}_1 - \check{e}_3]^T \\ & - 4F_5^T\check{e}_6^T - 6F_6^T\check{e}_6^T \Big\rangle_s + \check{e}_7(S_1 + S_2)\check{e}_7^T \\ & - (1 - h_D)\check{e}_8 S_1 \check{e}_8^T - \check{e}_9 S_2 \check{e}_9^T + \check{e}_2 \left(hS_5 + \frac{h^2}{2} S_6 \right) \check{e}_2^T \\ & - 2\check{e}_1 S_6 \check{e}_1^T + \frac{2}{h} \check{e}_1 S_6 \check{e}_5^T + \frac{2}{h} \check{e}_1 S_6 \check{e}_6^T + \frac{2}{h^2} \check{e}_4 S_5 \check{e}_5^T \\ & + \frac{2}{h^2} \check{e}_4 S_5 \check{e}_6^T - \frac{2}{h} \check{e}_4 S_5 \check{e}_4^T - \check{e}_5 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) \check{e}_5^T \\ & - \check{e}_5 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) \check{e}_6^T - \check{e}_6 \left(\frac{2}{h^3} S_5 + \frac{2}{h^2} S_6 \right) \check{e}_6^T \\ & + 2\check{e}_2(G_1 - K_1 + L_1)\check{e}_7^T + \check{e}_1(\bar{\Sigma}K_1 - \underline{\Sigma}G_1 + L_1\underline{\Sigma})\check{e}_2^T \\ & + \check{e}_1(\Sigma M_1 \Sigma - M_2 \Sigma_1)\check{e}_1^T + 2\check{e}_1 M_2 \Sigma_2 \check{e}_7^T - \check{e}_3 M_3 \Sigma_1 \check{e}_3^T \\ & + 2\check{e}_3 M_3 \Sigma_2 \check{e}_8^T - \check{e}_7(M_1 + M_2)\check{e}_7^T \\ & - \check{e}_8 M_3 \check{e}_8^T - \check{e}_4 M_4 \Sigma_1 \check{e}_4^T + 2\check{e}_4 M_4 \Sigma_2 \check{e}_9^T \\ & + \check{e}_2(-T_1 - T_1^T)\check{e}_2^T - \check{e}_9 M_4 \check{e}_9^T - 2\check{e}_1 W_0^T T_1^T \check{e}_2^T \\ & + 2\check{e}_2 T_1 W_1 \check{e}_7^T + 2\check{e}_2 T_1 W_2 \check{e}_8^T - 2e_1 T_2 \check{e}_2^T \\ & + \check{e}_1(-T_2 W_0 - W_0^T T_2^T)\check{e}_1^T + 2\check{e}_1 T_2 W_2 \check{e}_8^T \end{aligned}$$

$$\begin{aligned} & - 2\check{e}_2 T_3^T \check{e}_7^T - 2\check{e}_1 W_0^T T_3^T \check{e}_7^T + 2\check{e}_7 T_3 W_2 \check{e}_8^T \\ & + \check{e}_7(T_3 W_1 + W_1^T T_3^T)\check{e}_7^T - 2\check{e}_2 T_4^T \check{e}_8^T \\ & - 2\check{e}_1 W_0^T T_4^T \check{e}_8^T + \check{e}_7 W_1^T T_4^T \check{e}_8^T \\ & + \check{e}_8(T_4 W_2 + W_2^T T_4^T)\check{e}_8^T + 2\check{e}_1 T_2 W_1 \check{e}_7^T, \\ \widehat{\Pi}_1 = & \left\langle 2(\hat{e}_2 \quad 0) R_1(\hat{e}_1 \quad 0)^T - 4F_2^T \hat{e}_3^T - 6F_3^T \hat{e}_3^T \right. \\ & + 4F_5^T \hat{e}_1^T + 6F_6^T \hat{e}_1^T \Big\rangle_s, \end{aligned} \quad (60)$$

with

$$\langle \cdot \rangle_s = \frac{1}{2} [(\cdot) + (\cdot)^T], \quad (61)$$

$$\hat{e}_i = [0_{n \times (i-1)} \quad I_{n \times n} \quad 0_{n \times (9-i)}]^T \quad (i = 1, \dots, 9).$$

4. Numerical Examples

In this section, four numerical examples are given to show the effectiveness and improvement of the main results proposed in the paper.

Example 1. Consider the following neural networks of neutral type with discrete and distributed delays:

$$\begin{aligned} \dot{x}(t) = & -W_0 x(t) + W_1 f(x(t)) + W_2 f(x(t-h(t))) \\ & + W_3 \int_{t-r}^t f^T(x(s)) ds + W_4 \dot{x}(t-h(t)), \end{aligned} \quad (62)$$

where

$$\begin{aligned} W_1 = & \begin{bmatrix} -2.5573 & -1.3813 & 1.9574 & -1.1398 \\ -1.0226 & -0.8845 & 0.5045 & -0.2111 \\ 1.0378 & 1.5532 & 0.6645 & 1.1902 \\ -0.3896 & 0.7079 & -0.3398 & -2.2543 \end{bmatrix}, \\ W_2 = & \begin{bmatrix} 0.2853 & -0.0793 & 0.4694 & 0.5354 \\ -0.5955 & 1.3352 & -0.9036 & 0.5529 \\ -0.1497 & -0.6065 & -0.1641 & -0.2037 \\ -0.4348 & -1.3474 & -0.6275 & -2.2543 \end{bmatrix}, \\ W_3 = & \begin{bmatrix} 0.0265 & 0.1157 & 0.0578 & -0.0930 \\ 0.3186 & -0.1363 & -0.0859 & 0.0742 \\ 0.2037 & -0.2049 & 0.0112 & 0.1457 \\ -0.3161 & -0.2469 & -0.0736 & -2.2543 \end{bmatrix}, \\ W_4 = & \begin{bmatrix} -0.3054 & 0.3682 & 0.1761 & -0.0235 \\ -0.0546 & -0.2089 & -0.0754 & 0.2668 \\ 0.4563 & 0.0023 & 0.1440 & 0.6928 \\ -0.0115 & -0.2349 & 0.2004 & 0.1574 \end{bmatrix}, \\ W_0 = & \text{diag}\{1.6305, 1.9221, 2.5973, 1.3775\}, \\ \bar{\Sigma} = & \text{diag}\{1.0275, 0.9960, 0.3223, 0.2113\}, \\ \underline{\Sigma} = & \text{diag}\{0, 0, 0, 0\}. \end{aligned} \quad (63)$$

TABLE 1: Maximum allowable time-delay bounds $h = r$ in Example 1.

$h_D = 0$	[32]	$(m = l = 2)$ [39]	$(m = l = 3)$ [39]	$(l = 2)$ Theorem 6	$(l = 3)$ Theorem 6
$h = r$	1.8630	2.7442	3.0942	4.6531	4.8652

TABLE 2: Maximum allowable time-delay bounds $h = r$ for different values h_D in Example 1.

h_D	0.1	0.2	0.3	0.4	0.5	0.6	0.7	0.8	0.9
Theorem 6 ($l = 2$)	4.3682	4.1238	3.9862	3.6782	3.5132	3.1230	2.8623	2.5219	1.6725
Theorem 6 ($l = 3$)	4.5132	4.2685	4.1032	3.8658	3.7216	3.3275	2.9273	2.6312	1.7321

FIGURE 1: The simulation of Example 1 for $h = r = 4.8652$, where the initial value is $[-3, -2, 2, 3]^T$, $h_D = 0$, $l = 3$.

From Table 1, it can be seen that the stability criterion proposed in the paper is less conservative than those obtained by Feng et al. in [32] and Lakshmanan et al. in [39]. Besides, from Tables 1 and 2, the maximum allowable time-delay bounds h will become larger with the values of l becoming larger. Moreover, Figures 1 and 2 show that the state vector $x(t)$ stabilizes to zero asymptotically with different h_D and initial values. By using the Matlab LMI toolbox, we solve LMIs (13) and (14) for the case $h_D = 0$ and $h = 4.6531$ and obtain

$$P_{11} = \begin{bmatrix} 0.0048 & -0.0009 & 0.0017 & -0.0003 \\ -0.0009 & 0.0072 & -0.0010 & 0.0004 \\ 0.0017 & -0.0010 & 0.0045 & -0.0009 \\ -0.0003 & 0.0004 & -0.0009 & 0.0042 \end{bmatrix},$$

$$R_{211} = \begin{bmatrix} 0.0022 & -0.0012 & 0.0013 & -0.0004 \\ -0.0012 & 0.0043 & -0.0013 & 0.0006 \\ 0.0013 & -0.0013 & 0.0021 & -0.0007 \\ -0.0004 & 0.0006 & -0.0007 & 0.0015 \end{bmatrix},$$

$$R_{222} = \begin{bmatrix} 0.0063 & -0.0006 & 0.0011 & -0.0007 \\ -0.0006 & 0.0085 & -0.0015 & 0.0006 \\ 0.0011 & -0.0015 & 0.0050 & -0.0010 \\ -0.0007 & 0.0006 & -0.0010 & 0.0034 \end{bmatrix},$$

$$\begin{aligned} R_{311} &= \begin{bmatrix} 0.0030 & -0.0004 & 0.0006 & -0.0005 \\ -0.0004 & 0.0041 & -0.0009 & 0.0004 \\ 0.0006 & -0.0009 & 0.0026 & -0.0006 \\ -0.0005 & 0.0004 & -0.0006 & 0.0018 \end{bmatrix}, \\ Z_1 &= \begin{bmatrix} 0.0307 & -0.0024 & -0.0035 & -0.0050 \\ -0.0024 & 0.0181 & 0.0044 & -0.0137 \\ -0.0035 & 0.0044 & 0.0136 & -0.0027 \\ -0.0050 & -0.0137 & -0.0027 & 0.0302 \end{bmatrix}, \\ Z_2 &= \begin{bmatrix} 0.0022 & -0.0000 & -0.0003 & 0.0005 \\ -0.0000 & 0.0017 & -0.0000 & -0.0001 \\ -0.0003 & -0.0000 & 0.0026 & 0.0010 \\ 0.0005 & -0.0001 & 0.0010 & 0.0045 \end{bmatrix}, \\ S_1 &= \begin{bmatrix} 0.0065 & 0.0033 & 0.0006 & -0.0023 \\ 0.0033 & 0.0058 & 0.0017 & -0.0031 \\ 0.0006 & 0.0017 & 0.0049 & -0.0010 \\ -0.0023 & -0.0031 & -0.0010 & 0.0073 \end{bmatrix}, \\ S_2 &= \begin{bmatrix} 0.0066 & -0.0003 & -0.0016 & 0.0010 \\ -0.0003 & 0.0049 & 0.0006 & -0.0003 \\ -0.0016 & 0.0006 & 0.0052 & 0.0011 \\ 0.0010 & -0.0003 & 0.0011 & 0.0063 \end{bmatrix}, \\ T_1 &= \begin{bmatrix} 0.0087 & -0.0039 & 0.0032 & -0.0014 \\ -0.0037 & 0.0144 & -0.0017 & 0.0021 \\ 0.0030 & -0.0016 & 0.0061 & -0.0009 \\ -0.0007 & 0.0012 & -0.0017 & 0.0092 \end{bmatrix}, \\ T_2 &= \begin{bmatrix} 0.0131 & -0.0008 & 0.0044 & -0.0002 \\ -0.0043 & 0.0237 & -0.0074 & 0.0003 \\ -0.0012 & 0.0029 & 0.0099 & -0.0003 \\ -0.0016 & 0.0014 & -0.0025 & 0.0086 \end{bmatrix}. \end{aligned} \quad (64)$$

Example 2. Using this example, we will show the improvement of our results for (52) by two cases (A) and (B). Consider the following parameters as in [32, 39]:

Case A

$$W_0 = \begin{bmatrix} 6 & 0 & 0 \\ 0 & 5 & 0 \\ 0 & 0 & 7 \end{bmatrix},$$

$$W_1 = \begin{bmatrix} 1.2 & -0.8 & 0.6 \\ 0.5 & -1.5 & 0.7 \\ -0.8 & -1.2 & -1.4 \end{bmatrix},$$

TABLE 3: Maximum allowable time-delay upper bounds $h = r$ for $h_D = 0$ in Example 2.

$h_D = 0$	[9]	[45]	[46]	[12]	[21]	[39]	Theorem 13
Case A	4.3163	4.4697	4.3324	4.8374	4.4879	4.3763	4.9532
Case B	2.8266	2.9137	2.8317	2.7953	6.8279	7.2368	7.8698

FIGURE 2: The simulation of Example 1 for $h = r = 4.5312$, where the initial value is $[-0.8, -0.6, 0.4, 0.8]^T$, $h_D = 0.1$, $l = 3$. FIGURE 3: The simulation of Example 2 of Case A for $h = r = 4.9532$, where the initial value is $[-0.2, 0.5, -0.4]^T$, $h_D = 0$.

$$W_2 = \begin{bmatrix} -1.4 & 0.9 & 0.5 \\ -0.6 & 1.2 & 0.8 \\ 0.5 & -0.7 & 1.1 \end{bmatrix},$$

$$W_3 = \begin{bmatrix} -1.8 & 0.7 & -0.8 \\ 0.6 & 1.4 & 1 \\ -0.4 & -0.6 & 1.2 \end{bmatrix}, \quad (65)$$

$$\bar{\Sigma} = \begin{bmatrix} 0.5 & 0 & 0 \\ 0 & 0.5 & 0 \\ 0 & 0 & 0.5 \end{bmatrix}, \quad \underline{\Sigma} = \begin{bmatrix} 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}.$$

Case B

$$W_0 = \begin{bmatrix} 0.9 & 0 \\ 0 & 0.8 \end{bmatrix}, \quad W_1 = \begin{bmatrix} 1 & -1.7 \\ -1.6 & 1 \end{bmatrix},$$

$$W_2 = \begin{bmatrix} 1 & 0.6 \\ 0.5 & 0.8 \end{bmatrix}, \quad W_3 = \begin{bmatrix} 0.4 & 0.3 \\ 0.1 & 0.2 \end{bmatrix}, \quad (66)$$

$$\bar{\Sigma} = \begin{bmatrix} 0.25 & 0 \\ 0 & 0.25 \end{bmatrix}, \quad \underline{\Sigma} = \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix}.$$

For the above two Cases A and B of numerical examples, the maximum allowable upper bounds for guaranteeing the asymptotical stability of the corresponding systems obtained from Theorem 13 are listed in Table 3. Table 3 clearly shows

that our results have larger improvement over those results of previous literature. In Case A, when $h_D = 0$, $h = r$, the simulation result is given as Figure 3, which implies that under the given conditions, the state vector $x(t)$ stabilizes to zero asymptotically.

Example 3. Consider the following delayed neural network given in (47) with parameters:

$$W_0 = \begin{bmatrix} 2 & 0 \\ 0 & 2 \end{bmatrix}, \quad W_1 = \begin{bmatrix} 1.6 & 0.3 \\ 0.3 & 0.5 \end{bmatrix},$$

$$W_2 = \begin{bmatrix} 0.2 & 0.1 \\ 0.1 & 0.2 \end{bmatrix}, \quad W_4 = \begin{bmatrix} 0.15 & 0 \\ 0 & 0.15 \end{bmatrix}, \quad (67)$$

$$\bar{\Sigma} = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix}, \quad \underline{\Sigma} = \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix}.$$

The corresponding results for maximum allowable upper bounds of the time-varying delay $h(t)$ are given in Table 4. From Table 4, it can be clearly seen that the maximum allowable time-delay bounds h will become small with the values of h_D becoming large. Furthermore, when $h_D = 0.1$, the state trajectories of the system (47) are shown in Figure 4.

Example 4. In this Example, we give four Cases (A)–(C) that show the potential benefits and effectiveness of the developed

TABLE 4: Maximum allowable time delay bounds h for different values h_D in Example 3.

h_D	0.1	0.2	0.3	0.4	0.5	0.6	0.7	0.8	0.9
Theorem 11	9.0123	8.6789	8.4245	8.1237	7.9028	7.4532	7.1279	6.8325	6.0142

FIGURE 4: The simulation of Example 3 for $h = r = 9.0123$, where the initial value is $[-3, 3]^T$, $h_D = 0.1$.

method for delayed neural networks. Consider the delayed system (57) with the following parameters:

Case A

$$W_1 = \begin{bmatrix} -0.0373 & 0.4852 & -0.3351 & 0.2336 \\ -1.6033 & 0.5988 & -0.3224 & 1.2352 \\ 0.3394 & -0.0860 & -0.3824 & -0.5785 \\ -0.1311 & 0.3253 & -0.9534 & -0.5015 \end{bmatrix},$$

$$W_2 = \begin{bmatrix} 0.8674 & -1.2405 & -0.5325 & 0.0220 \\ 0.0474 & -0.9164 & 0.0360 & 0.9816 \\ 1.8495 & 2.6117 & -0.3788 & 0.8428 \\ -2.0413 & 0.5179 & 1.1734 & -0.2775 \end{bmatrix}, \quad (68)$$

$$W_0 = \text{diag}\{1.2769, 0.6231, 0.9230, 0.4480\},$$

$$\bar{\Sigma} = \text{diag}\{0.1137, 0.1279, 0.7994, 0.2368\},$$

$$\underline{\Sigma} = \text{diag}\{0, 0, 0, 0\}.$$

Case B

$$W_1 = \begin{bmatrix} 0.0530 & 0.0454 \\ 0.0987 & 0.2750 \end{bmatrix},$$

$$W_2 = \begin{bmatrix} 0.2381 & 0.9320 \\ 0.0388 & 0.5062 \end{bmatrix}, \quad (69)$$

$$W_0 = \text{diag}\{1.5, 0.7\}, \quad \bar{\Sigma} = \text{diag}\{0.3, 0.8\},$$

$$\underline{\Sigma} = \text{diag}\{0, 0\}.$$

TABLE 5: Maximum allowable upper bounds h for different h_D in Case A.

h_D	0.1	0.5	0.9
[36]	3.27	2.15	1.31
[37]	3.27	2.22	1.58
[38]	3.30	2.53	2.08
[47]	3.35	2.59	2.13
[48]	3.75	2.73	2.27
[49]	3.70	3.12	2.59
[50]	3.91	2.79	2.33
[42]	4.21	3.15	2.91
Theorem 15	5.19	3.92	3.36

TABLE 6: Maximum allowable time-delay upper bounds h in Case B.

$h_D = 0$	0.4	0.45	0.5	0.55
[36]	3.99	3.27	3.05	2.98
[48]	4.38	3.60	3.33	3.23
[49] ($m = 2$)	4.39	3.67	3.46	3.41
[19]	4.4801	4.0626	3.8083	3.7064
[18] ($m = 2$)	5.2420	4.4301	4.1055	3.9231
Theorem 1 in [51]	5.0588	4.2603	4.0604	4.0185
Theorem 2 in [51]	5.3079	4.5267	4.2924	4.1903
Corollary 1 in [51]	9.7094	7.7523	6.8570	6.2977
Theorem 15	10.2358	8.8378	7.9531	7.4532

Case C

$$W_1 = \begin{bmatrix} 1 & 1 \\ -1 & -1 \end{bmatrix}, \quad W_2 = \begin{bmatrix} 0.88 & 1 \\ 1 & 1 \end{bmatrix},$$

$$W_0 = \{2, 2\}, \quad \bar{\Sigma} = \text{diag}\{0.4, 0.8\}, \quad (70)$$

$$\underline{\Sigma} = \text{diag}\{0, 0\}.$$

From Tables 5, 6, and 7, it is clearly shown that Theorem 15 is less conservative than those in the mentioned literature. In Case A, when $h_D = 0.1$, the simulation result is given as Figure 5, which implies that under the given conditions, the state vector $x(t)$ stabilizes to zero asymptotically. Hence, this example indicates fully that the method proposed in the paper plays a major role in reducing conservatism.

Finally, we provide the number of decision variables involved in the LIM in each of the Theorems 6–15 in Table 8.

5. Conclusions

This paper is concerned with the stability analysis of neutral type neural networks with mixed time-varying delays. Some improved delay-dependent stability results are established by

TABLE 7: Maximum allowable time-delay bounds h for different values h_D in Case C.

Method	[52]	[48]	[53]	[42]	[54]	Theorem 15
$h_D = 0.8$	2.3571	2.8854	2.9144	3.1409	4.1626	6.9785
$h_D = 0.9$	1.6050	1.9631	1.9095	1.6375	3.9766	6.3457

TABLE 8: Number of decision variables involved in the stability criteria.

Method	Number of decision variables	Method	Number of decision variables
Theorem 6	$[(12 + l)^2 + 8(12 + l) + 6]n^2 + (16 + l)n$	Theorem 11	$215n^2 + 15n$
Theorem 13	$[(10 + l)^2 + 8(10 + l) + 6]n^2 + (14 + l)n$	Theorem 15	$159n^2 + 13n$

FIGURE 5: The simulation of Example 4 for $h = 5.19$, where the initial value is $[-0.2, 0.5, -0.4, 0.2]^T$, $h_D = 0.1$.

using a novel approach for the networks. Improved delay-dependent stability criteria in terms of linear matrix inequalities (LMIs) are derived by employing a new type of Lyapunov-Krasovskii functionals with three and four integral terms. Different from previous results by using the first-order convex combination property, our derivation applies the idea of second-order convex combination and the property of quadratic convex function. obtained results are formulated in terms of linear matrix inequalities (LMIs). Numerical examples are given to illustrate the effectiveness and the advantage of the proposed main results.

Acknowledgments

This work was supported by the National Basic Research Program of China (2010CB732501), the National Natural Science Foundation of China (61273015), and the Natural Science Foundation of Hainan province (111002).

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