

## Features Extraction of Motor Representations Using Neurofuzzy Networks

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**Abstract:** Motor imagery is the mental simulation of a motor act that includes preparation for movement, passive observations of action and mental operations of motor representations implicitly or explicitly. Motor imagery as preparation for immediate movement likely involves the motor executive brain regions. Implicit mental operations of motor representations are considered to underlie cognitive functions. Another problem concerning neuro - imaging studies on motor imagery is that the performance of imagination is very difficult to control. The ability of an individual to control its EEG may enable him to communicate without being able to control their voluntary muscles. Communication based on EEG signals does not require neuromuscular control and the individuals who have neuromuscular disorders and who may have no more control over any of their conventional communication abilities may still be able to communicate through a direct brain-computer interface. A brain-computer interface replaces the use of nerves and muscles and the movements they produce with electrophysiological signals and is coupled with the hardware and software that translate those signals into physical actions. One of the most important components of a brain-computer interface is the EEG feature extraction procedure. This paper presents an approach that uses self-organizing fuzzy neural network based time series prediction that performs EEG feature extraction in the time domain only. EEG is recorded from two electrodes placed on the scalp over the motor cortex. EEG signals from each electrode are predicted by a single fuzzy neural network. Features derived from the mean squared error of the predictions and from the mean squared of the predicted signals are extracted from EEG data by means of a sliding window. The architecture of the two auto-organizing fuzzy neural networks is a network with multi inputs and single output.

### 1 Introduction

Motor imagery is the mental simulation of a motor act that includes preparation for movement, passive observations of action and mental operations of motor representations implicitly or explicitly. Motor imagery as preparation for immediate movement likely involves the motor executive brain regions. Implicit mental operations of motor representations are considered to underlie cognitive functions. Another problem concerning neuro imaging studies on motor imagery is that the performance of imagination is very difficult to control. Most studies have relied on subjective evaluation and not objective confirmation, of task performance. A series of neuro imaging studies on mental operations have successfully evaluated behavioural performance without involving any motor response during task periods by taking subjects into following sensory stimuli applied serially to update mental representations during the task and then report the final image at the end of the task. Motor imagery is a dynamic state in which a

subject mentally simulates a given action. This work presents a procedure for extracting features from the electroencephalogram (EEG) recorded from subjects involving motor imagery. Two auto-organizing fuzzy neural networks are used to perform prediction tasks for the EEG data. Features are taken from the mean squared error in prediction and from the mean squared of the predicted signals. Linear analysis is used for classification of signals. This extraction procedure is tested offline on two subjects leading to classification accuracy rates near 83% with information transfer rates near 8 bits/min. This approach shows good potential for online feature extraction and autonomous system adaptation. The ability of an individual to control its EEG may enable him to communicate without being able to control their muscles. Communication based on EEG signals does not require neuromuscular control and the individuals who have neuromuscular disorders and who may have no more control over any of their conventional communication abilities may still be able to communicate through a direct brain-computer interface. A brain-computer interface replaces the use of nerves and muscles and the movements they produce with electrophysiological signals and is coupled with the hardware and software that translate those signals into physical actions. One of the most important components of a brain-computer interface is the EEG feature extraction procedure. This paper presents an approach that uses self-organizing fuzzy neural network based time series prediction that performs EEG feature extraction in the time domain only. EEG is recorded from two electrodes placed on the scalp over the motor cortex. EEG signals from each electrode are predicted by a single fuzzy neural network. Features derived from the mean squared error of the predictions and from the mean squared of the predicted signals are extracted from EEG data by means of a sliding window. The architecture of the two auto-organizing fuzzy neural networks is a network with multi inputs and single output. The use of auto-organizing fuzzy neural networks is convenient for applications because the auto-organizing fuzzy neural network can adapt itself to each individual's EEG signals so that very little subject specific knowledge or parameter selection is required. It can perform online learning thus has potential for continuous learning and continuous adaptation to the dynamics of each individual's EEG signals. Chapter 1 of the paper presents the data configuration. Chapter 2 gives the description of the results and conclusions.

## **2 Data Configuration**

### 2.1 Acquisition of EEG data

The data is recorded from two subjects in a timed experimental recording procedure where the subject is instructed to imagine moving the left and right hand in accordance to a directional cue displayed on a monitor. In each recording session a number of EEG patterns correlated to the imagined right or left arm movement are produced by a subject over a number of trials. Recorded EEG signals are sampled at 120 Hz and filtered between 0.5 and 30 Hz [4].

## 2.2 Configuration of EEG data

The EEG data recorded from each electrode is configured so that the measurements from time instants  $t-5$  to  $t-1$  are used to make a prediction of the measurement at time  $t$ . Each training data input exemplar contains five measurements from the data recorded from either the C1 or C2 electrode. The training data output contains every subsequent measurement  $t$  from each of the input data vectors. The extracted input-output data vector for the time series C1 and C2 are like in (1) and (2).

$$[c_1(t-5); c_1(t-4); c_1(t-3); c_1(t-2); c_1(t-1); c_1(t)] \quad (1)$$

$$[c_2(t-5); c_2(t-4); c_2(t-3); c_2(t-2); c_2(t-1); c_2(t)] \quad (2)$$

Every trial has 5 seconds of task related data. The data is recorded from two subjects, S1 and S2. There were 300 trials recorded for subject S1 and 300 trials recorded for subject S2, an equal number of trials for each type of movement imagery. Each trial consists of 600 samples ( $5s/120-1s = 600$ ). There are 595 training data pairs for each trial, samples 595 to 599 are used to predict the sample 600.

## 2.3 Neurofuzzy architecture

Two auto-organizing fuzzy neural networks are used to perform prediction. One auto-organizing fuzzy neural network is trained for the left EEG data and the other one auto-organizing fuzzy neural network for right EEG data. By using separate auto-organizing fuzzy neural networks for each type of data, it is desired that each trained auto-organizing fuzzy neural networks develop certain uniqueness, in that it is more apposite to each type of time series data [4]. The advantage of using a self-organizing structure, like that of the auto-organizing fuzzy neural networks, is that the problem of specifying the network's architecture does not have to be considered [5]. For the neural networks, finding the optimum architecture for a particular task can be very problematic and does have a significant effect on the performances. Auto-organizing fuzzy neural networks are hybrid systems that combine the theories of fuzzy logic and neural networks. In hybrid systems like the self-organizing fuzzy neural networks, the fuzzy techniques are used to create or improve certain aspects of the neural network's performance. An important advantage of the auto-organizing fuzzy neural network is the generation of a model from observations of complex systems where little insufficient expert knowledge is available to describe the behavior, as is the case for EEG data [6]. The auto-organizing fuzzy neural networks can deal with characteristics of EEG such as large dimensions and noise to provide a model that can be used for interpretation of the EEG. This is another advantage of using an auto-organizing fuzzy neural network for EEG analysis. The auto-organizing fuzzy neural network is designed to

approximate a fuzzy process of fuzzy inference through the structure of neural network and thus create an interpretable hybrid model of neural network using the superior learning ability of neural networks and easy interpretability of fuzzy systems. The dynamic adaptation of the structure of the hybrid network captures the underlying behavior of a nonlinear time-varying complex system more easily and accurately. The online learning algorithm, based on a hybrid recursive least squares estimator, and an autonomous neuron adding and pruning structure based on the optimal brain surgeon technique, provide a truly online learning algorithm for modeling/predicting the highly non-stationary EEG signal [4].

#### 2.4 EEG features extraction procedure

Each self-organizing fuzzy neural network is a multi-input-single-output (MISO) network so only EEG data recorded from a single electrode can be predicted. The system is configured in three stages [4]. The first stage involves training of the two auto-organizing fuzzy neural network separately to perform one-step-ahead prediction, using five previous measurements of each time series. The two auto-organizing fuzzy neural network are named 'L' for the left data-electrode C1 and 'R' for right data electrode C2 corresponding to the type of EEG data on which they are trained, either left or right motor imagery. The second stage implies input of each type of training data, the same data used to train the auto-organizing fuzzy neural networks into each of the auto-organizing fuzzy neural networks. All the 'L' training data is input to both the 'L' and 'R' network, then all the 'R' training data is input to both 'L' and 'R' network in a similar manner. Each auto-organizing fuzzy neural network provides a one-step-ahead prediction for the data in for each trial. When a trial is input to all of the two auto-organizing fuzzy neural networks, features are extracted by calculating the mean square error (MSE) of the prediction for a portion of the trial and the mean squared of the actual prediction (MSA). As these calculations gives predictions over a segment to a scalar value, EEG features based on the error and on predicted signal can be obtained as in (3).

$$fy_k = \frac{1}{M} \left( \sum_{t=1}^M (y(t) - \hat{y}_k(t))^2 + \sum_{t=1}^M (\hat{y}_k(t))^2 \right) \quad (3)$$

Equation (3) is used for obtaining each feature, where  $y(t)$  is the actual signal and  $\hat{y}_k(t)$  is the predicted signal. The 'k' index is used to show whether the signal is from left 'l' or right 'r' auto-organizing fuzzy neural network. M is the number of prediction samples used. The extracted features are in vector form, the feature vector  $fv$ , is shown in Figure 1. For each trial a two elements feature vector is obtained and classes of features for right and left data can be obtained by entering all trials of training data into the auto-organizing fuzzy neural networks in Figure

1. Normalizing the features (i.e. dividing each feature vector by the sum of the components within the vector) can reduce the intra class variance – a fundamental goal of any feature extraction procedure. Features can be extracted for every time point in a trial using a sliding window approach. To extract a new set of features for every time point in a trial using the sliding window approach,  $t$  ranges from  $t=s$  to  $M$  where  $s$  and  $M$  are incremented before the next set of features is extracted (initially  $s=1$  and  $M=\text{window size}$ ). This means that data at the beginning of a trial is forgotten as the window slides away from the start of the trial. The of using the sliding window for feature extraction is that the feature extraction procedure does not require knowledge about the point at which communication is initiated by the user and so online feature extraction can be realized [4].

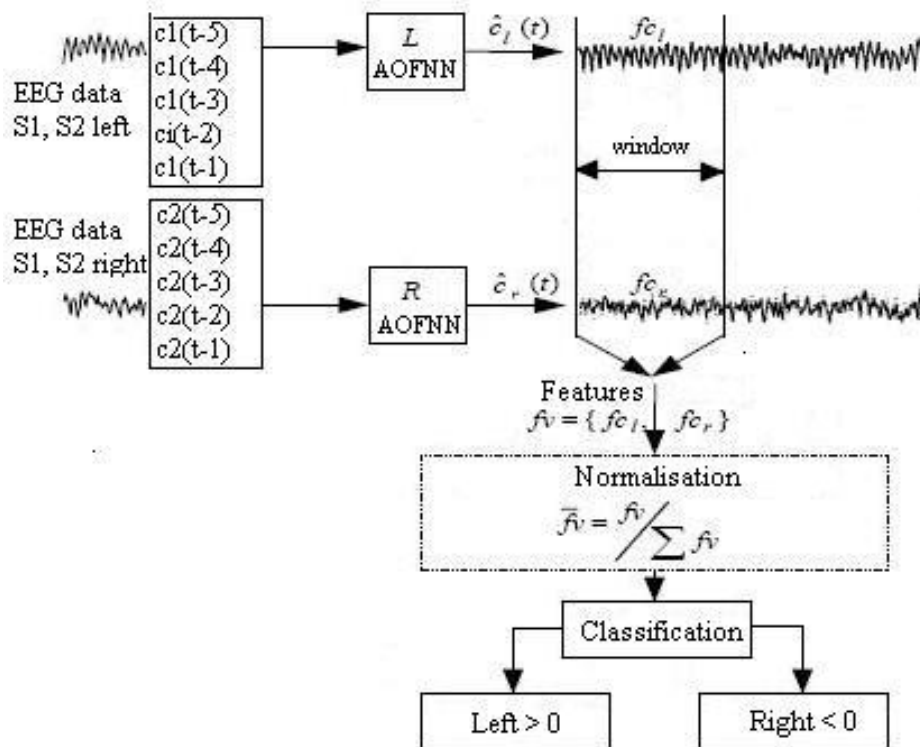


Fig. 1 - EEG feature extraction procedure

## 2.5 Data classification

The last step is the data classification performed using linear discriminant analysis, a classifier that works on the assumption that different classes of features can be separated linearly. Linear classifiers are more reliable than the nonlinear ones because they have limited flexibility. Experimentation involved extraction and

classification of features at every time point in a trial, allowing selection of the optimum time points to perform feature extraction and classification for more effective deployment of the system. This approach allows features to be extracted at the rate of the sampling interval [4].

### 3 Results and Conclusions

#### 3.1 Results

The system was tested on 150 trials for subject S1 and 150 trials for subject S2. The obtained results are shown in Table 1.

Table 1

Results

Subject	Normalisation	Window size	Classification accuracy [%]	Time [s]	Rate [bpm]
S1	No	310	76.34	3.43	6.89
	Yes	320	82.68	3.62	7.27
S2	No	300	70.63	3.24	6.43
	Yes	340	79.87	4.13	7.68

The first column specifies the subject. The second column specifies whether normalized features were used. Column three specifies the sliding window size. Column four indicates classification accuracy rate, column five shows the time elapsed for classification and column six shows IT rates. All results in bold specify the best results obtained for each type of performance quantifier. All IT rates were calculated using the time interval between communication start meaning the second 4 of timing scheme and the point that maximum classification accuracy was obtained. This provides good indication about the maximum IT rate a system can achieve whilst system accuracy is optimal. IT rates can be much higher if calculated in the first second of a trial, even if classification accuracy is lower. Irregular transients in the signals, caused by noise or artifacts did not have as much affect on the features because the auto-organizing fuzzy neural networks did not predict irregular transients in the signal that indicates that the auto-organizing fuzzy neural networks aided to the removal of artefacts and noise for subjects S1 and S2. Normalizing the features produces higher classification accuracy and IT rates that is because normalization reduces the intra-class variability. The number of neurons in each auto-organizing fuzzy neural network was different from its counterparts due to variations in the types of signals on which each auto-organizing fuzzy neural network was trained.

### 3.2 Conclusions

No artifact removal or noise reduction was carried out on the raw EEG data from subjects that indicates the robustness of this approach. However, the number of neurons in each auto-organizing fuzzy neural network increased when noise increased. This approach shows good potential for online EEG feature extraction and can be further developed by implementing a multiple-step-ahead prediction technique. The system can perform online adaptation because it can autonomously add neurons to accommodate to the variations in the EEG data.

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