Resultados de prueba de plagio: org-076.txt

Plagio detectado: 77.51%

Texto original: ï»¿This article delves into the intricacies of adaptive fuzzy event-triggered formation tracking control for nonholonomic multirobot systems characterized by infinite actuator faults and range constraints.

Texto plagiado: ï»¿This article delves into the intricacies of adaptive fuzzy event-triggered formation tracking control for nonholonomic multirobot systems characterized by infinite actuator faults and range constraints.

Texto original: To address these issues, we leverage the power of fuzzy logic systems (FLSs) and employ adaptive methods to approximate unknown nonlinear functions and uncertain parameters present in robotic dynamics.

Texto plagiado: To address these issues, we leverage the power of fuzzy logic systems (FLSs) and employ adaptive methods to approximate unknown nonlinear functions and uncertain parameters present in robotic dynamics.

Texto original: In the course of information exploration, the problems of collision avoidance and connectivity maintenance are ever present due to limitations of distance and visual fields.

Texto plagiado: In the course of information exploration, the problems of collision avoidance and connectivity maintenance are ever present due to limitations of distance and visual fields.

Texto original: Furthermore, to reduce the number of controller executions and compensate for any effect arising from infinite actuator failures, robots engage with their leader at the moment of actuator faults using fewer network communication resources yet maintain uninterrupted tracking of the desired trajectory generated by the leader.

Texto plagiado: Furthermore, to reduce the number of controller executions and compensate for any effect arising from infinite actuator failures, robots engage with their leader at the moment of actuator faults using fewer network communication resources yet maintain uninterrupted tracking of the desired trajectory generated by the leader.

Texto original: We guarantee that all signals are semi-global uniformly ultimately bounded (SGUUB).

Texto plagiado: We guarantee that all signals are semi-global uniformly ultimately bounded (SGUUB).

Texto original: Ultimately, we demonstrate the practical feasibility of the ETFT control strategy for nonholonomic multirobot systems.

Texto plagiado: Ultimately, we demonstrate the practical feasibility of the ETFT control strategy for nonholonomic multirobot systems.