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Texto plagiado: 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.

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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.

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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.

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