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Nota di contenuto	Introduction -- Distributed localisation for MASs under barycentric coordinate representation -- Distributed localization of MASs with imperfect channel -- Distributed localization of MASs with random noise -- Distributed localization of MASs with randomly varying trajectory lengths -- Data-driven adaptive distributed localization of MASs with sensor failure -- Distributed sensor network localization based on local bearing measurement -- Local-bearing-based prescribed-time localization of MASs with noisy measurement -- Integration of distributed localization and formation of MAS.
Sommario/riassunto	This book mainly focuses on the key technologies and important issues related to localization estimation and formation control for networked multi-agent systems. Chapter 1 introduces the concepts of multi-agent

systems, fundamental issues in localization and formation, research progress both at home and abroad, and the theory of system stability. Chapters 2–8 present research results on distributed localization estimation under conditions such as random deployment, non-ideal channels, random noise, varying-trajectory length, sensor multiplicative failure, and local bearing measurement. Chapter 9 focuses on integrated research progress in localization estimation and formation control for multi-agent systems under local perception conditions. The book demonstrates the effectiveness and superiority of the theoretical methods through simulation and physical examples.