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This book deals with locomotion control of biologically inspired robots realized through an analog circuit paradigm as cellular nonlinear networks. It presents a general methodology for the control of bio-inspired robots and several case studies, as well as describes a new approach to motion control and the related circuit architecture. Bio-inspired Emergent Control of Locomotion Systems provides researchers with a guide to the fundamentals of the topics. Moreover, neuro-biologists and physiologists can use the book as a starting point to design artificial structures for testing their biological hypotheses on the animal model.