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Sommario/riassunto	This book focuses on pneumatic servo systems analysis, control and application in robotic systems. The pneumatic servo systems are composed by pneumatic artificial muscles or cylinders, which are two important pneumatic actuators in industrial application. The active disturbance rejection control technique is used effectively to solve strong nonlinearity and uncertain factors for the pneumatic servo systems. Nonlinear feedback control, back-stepping control, finite-time control, sliding mode control and several other control laws are proposed to make the pneumatic servo systems have better control performances. The book establishes a fundamental framework for this topic, while emphasizing the importance of integrated analysis. The book is intended for undergraduate and graduate students who are interested in this field and engineers working on the applications of

pneumatic servo systems. Advances in Industrial Control reports and encourages the transfer of technology in control engineering. The rapid development of control technology has an impact on all areas of the control discipline. The series offers an opportunity for researchers to present an extended exposition of new work in all aspects of industrial control.