



SDI Review Form 1.6

Journal Name:	British Journal of Mathematics & Computer Science
Manuscript Number:	2014_BJMCS_10905
Title of the Manuscript:	Energy-Based L_2 -Disturbance Attenuation Control for Robot Manipulator With Uncertainties and Input Delay
Type of the Article	Original Research Article

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This journal's peer review policy states that **NO** manuscript should be rejected only on the basis of '**lack of Novelty**', provided the manuscript is scientifically robust and technically sound.

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PART 1: Review Comments

	Reviewer's comment	Author's comment (if agreed with reviewer, correct the manuscript and highlight that part in the manuscript. It is mandatory that authors should write his/her feedback here)
Compulsory REVISION comments	Compared with [Wang (2008)], the main innovation is that a delay of the system has been investigated. However, in your control law, in order to solve the control input in time ($t-h$), the information in time (t) is required. How can you know the states of the system in time (t).	First, the authors would like to express their sincere thanks to the reviewer for his/her valuable suggestions, and the time and efforts he/she has spent in the review. Without the expert comments made by the reviewer, the paper would not be of this quality. All the comments made by the reviewer have been carefully addressed with our best efforts in the revised version. In this paper, the control signals under consideration include two parts: the local control signals and the remote control signals. As the result of acquisition and transmission of the sensor signals, time delays of remote control part are considered. In the new version, we have revised the expression of control τ for more accurate understanding.
gesMinor REVISION comments	In the manuscript a planar two-link manipulator is given as an example for the fully actuated case. Please add an example for the underactuated case.	Thank you for this suggestion. As the analysis in Section 3, in the underactuated case, we can obtain the solution group of (3.6) by using MATLAB. Then we can get the pre-feedback law by the simple mathematical ideas. Consequently, with the pre-feedback law, we can obtain the same Hamiltonian formulation (3.3) as the fully actuated case in this paper. Thus, in order to avoid too much repetition and make the paper compact, we did not add an example for



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		the underactuated case.
<u>Optional/General</u> comments	The interpretations according to Figs. 2-6 should be given in more detail. And please highlight the response characteristics of delay in the figures.	This is a very good suggestion for improving the presentation of the results in the paper. According to the reviewer's suggestion, the interpretations according to the figures have been given in more detail in Section 5 in the new version. Besides, in order to highlight the response characteristics of delay in the figures, we reset the initial point of the simulation and different delays are given to illustrate the effectiveness of the proposed control design scheme (please refer to Figures 2-10).