



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

General guideline for Peer Review process:

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	Its publication can be recommended after considering the following points: 1. What is the physical meaning of time delay in the real working condition? Whether time delays are reasonable or can be satisfied in the engineering applications? 2. What is the meaning of $\varphi(t)$ in the pre-feedback law(3.1)? 3. In section 5, the illustration of the simulation is too simple and lack of comparison with other control laws, so we can see the advantages of the controller designed in this paper. 4. The whole manuscript should be revised for some typewriting and syntax errors. It will be better for the authors to check this paper carefully.	First, the authors would like to express their sincere appreciation to the reviewer for his/her constructive comments and suggestions provided, 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. 1. To the first comment, our response is: In the actual working condition, many factors, such as acquisition and transmission of the sensor signal, the calculation of the controller, actuation process of the actuator, can lead to time delays appear in the system. In robot manipulator, transmission of the sensor signal is essential and the signal can be regard as the input value. Therefore, time delays are reasonable in the engineering applications. 2. To the second comment, our response is: Thanks for this question. We did not express clearly on this in the old version. $\varphi(t)$ is a continuous vector-valued initial function of $\hat{\theta}(t)$. In fact, $\varphi(t)$ is a component of $\phi(t)$. An explanation has been added to answer this question in the new version (please see the highlight of page 4). 3. To the third comment, our response is: This is a very good suggestion for improving the presentation of the results in the paper. According to this reviewer's suggestion, we have expanded the content of the simulation part and compared our result with others in the new version (please refer to Section 5). However, it is worth to point out that the comparison is mainly about the effect of the proposed controller applied to the system under consideration when delays occur.



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		4. To the last comment, our response is : The authors have proofread the paper carefully and all the typos and syntax errors have been corrected in the revised version.
<u>Minor</u> REVISION comments		
<u>Optional/General</u> comments		