



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.

To know the complete guideline for Peer Review process, reviewers are requested to visit this link:

(<http://www.sciencedomain.org/page.php?id=sdi-general-editorial-policy#Peer-Review-Guideline>)



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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)
<u>Compulsory</u> 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).	
<u>Minor</u> 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 under actuated 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.	

Note: Anonymous Reviewer