



**SDI Review Form 1.6**

Journal Name:	<a href="#">Physical Science International Journal</a>
Manuscript Number:	_2015_PSIJ_18253
Title of the Manuscript:	<b>Robustness Analysis of a Closed-Loop Controller for a Robot Manipulator in Real Environments</b>
Type of the 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**

	<b>Reviewer's comment</b>	<b>Author's comment</b> <i>(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)</i>
<b><u>Compulsory</u></b> REVISION comments	<p>This paper is about the robustness analysis of a closed loop controller for a robot manipulator in real environment. It is an application of a basic and well known robust control methodology. It is not a “recent advance in robust control design methodology” as authors write in section 3. All the techniques presented in section 4 relative to robustness analysis are well known in control. I consider this paper could be interesting for a reader who wants to learn basic principles of robust control. For instance, it could be appropriate for a control student to understand basic principles of robust control.</p> <p>I consider a real application with a real plant or a comparison with different controllers (fuzzy for instance), not only the classical PID presented in the manuscript could improve substantially the paper.</p>	<p>The correction was made.</p>
<b><u>Minor</u></b> REVISION comments		
<b><u>Optional/General</u></b> comments		