



SDI Review Form 1.6

Journal Name:	Physical Science International Journal
Manuscript Number:	_2015_PSIJ_18253
Title of the Manuscript:	Robustness Analysis of a Closed-Loop Controller for a Robot Manipulator in Real Environments
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:

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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	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. 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.	
<u>Minor</u> REVISION comments		
<u>Optional/General</u> comments		

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