SDI Review Form 1.6

Journal Name:	Journal of Engineering Research and Reports
Manuscript Number:	**Ms_JERR_53565**
Title of the Manuscript:	**Robust Control for a 3DOF Articulated Robotic Manipulator Joint Torque under Uncertainties**
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)

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	**The paper brings no novelty, but the application of a robust control technique to a 3DOF articulated robotic manipulator joint torque seems to be an acceptable contribution to the JERR.** **The Abstract contains an unnecessarily high amount of details related to the results (dB). They fit more into the Conclusion. Please make the Abstract better arranged and more readable.** **Many symbols are mutually inconsistent from the formal viewpoint.** **The English should be improved.**	The manuscript has been thoroughly modified
Minor REVISION comments		
Optional/General comments		

PART 2:

	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)*
Are there ethical issues in this manuscript?	*(If yes, Kindly please write down the ethical issues here in details)*	