

Review of: "Fault-tolerant scheme for robotic manipulator—Nonlinear robust back-stepping control with friction compensation"

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Potential competing interests: The author(s) declared that no potential competing interests exist.

The paper is written good but it needs some more corrections.

Paper's English should be enhanced. Comparative literature review is missing.

explain the contribution of this manuscript over and above the state of art and establish its novelty.

(1) Why is the LuGre friction model used? The effects of this friction model and similar models have not been discussed in detail in the literature. You should compare the proposed friction model with other models in the literature.

(2) Comparison of FTC controller performance compared to traditional controllers.

(3) Should be cited articles about friction. References are not updated. You should look at the papers: A comparative study of the joint neuro-fuzzy friction models for a triple link rotary inverted pendulum, ZB Hazem, MJ Fotuhi, Z Bingül, IEEE Access 8, 49066-49078.