Review Form 1.7

Journal Name:	**Journal of Engineering Research and Reports**
Manuscript Number:	**Ms_JERR_118899**
Title of the Manuscript:	**Structure design and analysis of welding robot manipulator**
Type of the Article	

Review Form 1.7

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 1. **Is the manuscript important for scientific community?** (Please write few sentences on this manuscript) 2. **Is the title of the article suitable?** (If not please suggest an alternative title) 3. **Is the abstract of the article comprehensive?** 4. **Are subsections and structure of the manuscript appropriate?** 5. **Do you think the manuscript is scientifically correct?** 6. **Are the references sufficient and recent? If you have suggestion of additional references, please mention in the review form.** **(Apart from above mentioned 6 points, reviewers are free to provide additional suggestions/comments)**	**Yes**, a manuscript focusing on important parameters in industrial robot manipulator design would be significant for the scientific community and the growing field of industrial robots. Optimizing manipulator design can greatly enhance robot performance and efficiency by identifying and analyzing key parameters for optimization. **Yes** It appears that the article's abstract is **not** comprehensive. An ideal abstract should summarize the research question, methodology, and key findings. **No** **No** **Yes**	
Minor REVISION comments 1. **Is language/English quality of the article suitable for scholarly communications?**	Yes	
Optional/General comments	Abstract: The abstract should be revised to provide a clear explanation of the significance, methodology, and design process. It should also highlight the key design outcomes and the most important conclusions. Introduction: The introduction needs to underscore the importance of the research and the potential in developing industrial robots. Additionally, it should offer a brief literature review related to the topic. Theoretical Aspect: It is essential to define the type of manipulator slated for design by specifying the number of degrees of freedom and determining the required joints. The design process should be clearly outlined along with detailed drawings featuring dimensions. Furthermore, it's important to define the fundamental equations used and cite the sources from which these equations were derived. : Results The results section should be clarified by emphasizing the most pivotal dimensions, joint diameters, and other critical design considerations. In cases where specific data is not found, the plan should be adjusted to align with the key outputs. The figures in the manuscript are not clear enough to be easily interpreted and understood. What are the angle values for the movability of cylinder M and the lifting cylinder K, and what are their respective speed values? Conclusions: The conclusions should cohere with the theoretical research and the obtained results. Clearly stating that the manipulator has three degrees of freedom should be presented as a hypothesis rather than a conclusion.	

	Please find the reviewed manuscript attached for more details.	

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)*	

Reviewer Details:

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