

CONTROL ENGINEERING AND APPLIED INFORMATICS JOURNAL

DECLARATION

I hereby certify that the paper entitled **Lyapunov-Based Nonlinear Disturbance Observer for n-Links Flexible Joint Robot Manipulators** written by the authors **A. Nikoobin, A. Habibollahi and A. Dideban** presents the original results of our research activity. We warrant that the above work has not been previously published elsewhere.

_____4 April 2016_
Date

Original signature of the first author

Amin Nikoobin

A handwritten signature in blue ink, consisting of a large loop at the top and several horizontal strokes at the bottom.

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