

In this paper, a pre-defined time fuzzy controller considering external disturbance and model uncertainty is proposed. First, a predefined time controller is proposed based on the barrier Lyapunov function. Second, a predefined temporal fuzzy logic system is developed to approximate external disturbances and model uncertainties. And the dynamic relative threshold event trigger mechanism is improved, which saves the communication resources of the robot. However, the study has some flaws that require major revisions before this manuscript can be accepted for publication:

- 1) The authors should carefully review the manuscript and correct grammar and writing errors.
- 2) There is a problem with the format of formula 1, please pay attention to check.
- 3) The formulas in the manuscript are too messy, please confirm whether each formula is necessary for readers to read.
- 4) There are many notations in the manuscript that are not defined, for example, q in formula 1 in line 122 is not defined.
- 5) Are LiL and UiL in line 202 constants or functions? If they are functions, what is their domain? Why is there no definition in the manuscript?
- 6) How to see the barrier function of $LL1$ and $LU1$ in Figure 4?
- 7) At present, there are many results for multi-robot cooperative control, such as “doi: 10.1016/j.automatica.2021.109988”. Compared with the existing results, the main contributions of this paper need to be further strengthened.

Please address these revisions in order to improve the manuscript before submission.