This paper provides design and fabrication methods for three types of fluidic elastomeric actuators along with a brief review of related work. Example applications for each type of actuator are presented. Some preliminary data comparing the actuators based on fluidic volume, energy, displacement and tip force are presented for the three actuators. Details regarding the geometric parameters for the compared actuators are not provided, making the comparison less meaningful. The paper will benefit if these are clearly stated in the paper.

Other comments:
1. The organization can be improved. For instance 2.3.1 and 2.3.2 are not fabrication methods.

2. Sec. 2.1.3, line 3. It is stated "FEA is a bending actuator". FEA is not necessarily a bending actuator. There can be extension, twisting and other complex motions. Please reword.

3. Sec. 3.2.4 Please provide pictures or schematics of experimental setup, especially for tip force measurements.

4. The remarks in Sec. 3.2.4 , seem to ignore the characteristics at lower volumes and fluid energy. Please state clearly the domain in which the statements are valid.

5. For a given fluid energy input the bending angle for the cylindrical actuator is the least while the tip force is highest (when J<2). A discussion regarding this may be insightful for designing such actuators.

6. In Sec. 3.2.4, what limits the energy input to the other actuators relative to the pleated actuators?