Review of: "Optimal Latency Compensator for Improved Performance of Teleoperated UGVs on Soft Terrains"

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Potential competing interests: No potential competing interests to declare.

- The title is clear and concise, providing a straightforward indication of the main subject matter. It effectively conveys that the research deals with optimizing latency compensators for enhancing the performance of teleoperated Unmanned Ground Vehicles (UGVs), specifically on soft terrains.
- The title addresses a significant issue in the field of robotics and autonomous systems - the performance of teleoperated UGVs on soft terrains, which is a challenging scenario.
- The paper effectively addresses a crucial problem: the impact of latency on UGV maneuvering and performance in teleoperation systems.
- The inclusion of a latency threshold (0.72 seconds) and Mean Delay Compensation Percentage (86%) provides quantitative measures that enhance the clarity of the study's outcomes. The GA-optimized predictor is not mentioned clearly in the Human-In-The-Loop Experiment.
- The author states that these observations (completion time and mission success rate) indicate a high likelihood of achieving the desired outcome. This implies that the task was completed efficiently within a reasonable time frame, and there is confidence in the success of the mission.
- The mention of increased overshoot and unused energy could be strengthened by providing additional context or potential reasons for these observations. Offering insights into mitigating these issues could further enhance the discussion.