# 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.

Well, interesting work.

It would be interesting and convenient to see more details about the effect of operating the platform under different nominal speed conditions.

I presume that, in those cases, at certain high cruise speeds, the traction may fail more frequently, requiring the controller to deal with a more challenging task in which delays would be highly critical disturbances, in addition to those related to slippage, etc.

Finally, some discussion may have been included to justify the need for closing the loop remotely in respect to a semi-autonomous approach, in which part of the control would operate on the platform itself, exploiting local perception (which would not be affected by any delays at all), giving the remote operator (or high-level controller) the mission to specify some high-level “set-points,” and giving the UGV the task of performing perception (e.g., terrain mapping), short-term