Our research, “Optimized Tactical Pathing for Unmanned Ground Vehicles”, is an optimization and modeling tool designed to determine the safest path for an unmanned ground vehicle. The primary stakeholder for this project is the Army Research Laboratory. The key advantage of this tool is its novel approach to energy optimization while accounting for the locations of multiple enemies. However, deploying this tool without proper testing in a combat environment poses potential risks to the stakeholder. Several assumptions made in our simulation may not accurately reflect real-world conditions. For instance, our enemy detection code generates a theoretical detection map that has not been validated against actual enemy perception, as quantifying detection remains challenging. Additionally, our battery model does not factor in the vehicle’s exact weight, as those specifications are classified. Furthermore, the path nodes in our model are spaced 10 meters apart, which disregards obstacles that may exist between nodes due to the discretization. These are just a few of the many assumptions outlined in our paper. If deployed without thorough testing, our model could lead to the loss of both equipment and personnel. To mitigate this risk, extensive testing and validation are essential before real-world implementation. It is our responsibility to clearly communicate the model’s limitations to the Army Research Labratory before handing it over for testing and use in combat.