



## NASA SBIR 2014 Phase I Solicitation

### S4.02 Robotic Mobility, Manipulation and Sampling

Lead Center: JPL

Participating Center(s): ARC, GSFC, JSC

Technologies for robotic mobility, manipulation, and sampling are needed to enable access to sites of interest and acquisition and handling of samples for in-situ analysis or return to Earth from planetary and solar system small bodies including Mars, Venus, comets, asteroids, and planetary moons.

Mobility technologies are needed to enable access to crater walls, canyons, gullies, sand dunes, and high rock density regions for planetary bodies where gravity dominates, such as the Moon and Mars. Trafficability challenges include steep terrain, obstacle size, and low soil cohesion. Tethered systems, non-wheeled systems, and marsupial systems are examples of mobility technologies that are of interest. Technologies to enable mobility on small bodies in micro-gravity environments are also of interest.

Manipulation technologies are needed to enable deployment of sampling tools and handling of samples. Mars mission sample-handling technologies are needed to enable transfer and storage of a range of rock and regolith cores approximately 1cm long and up to about 10cm long. Small-body mission manipulation technologies are needed to deploy sampling tools to the surface and transfer samples to in-situ instruments and sample storage containers.

Sample acquisition tools are needed to acquire samples on planetary and small bodies. For Mars, a coring tool is needed to acquire rock and regolith cores approximately 1cm diameter and up to 10cm long which also supports transfer of the samples to a sample handling system. Abrading bits for the tool are needed to provide rock-surface abrasion capability to better than 0.2mm scale roughness. A deep drill is needed to enable sample acquisition from the subsurface including rock cores to 3m depth and icy samples from deeper locations. Tools for sampling from asteroids and comets are needed which support transfer of the sample for in-situ analysis or sample return. Tools for acquisition and transfer of icy samples on Europa are also of interest. Minimization of mass and ability to work reliably in the harsh mission environment are important characteristics for the tools. Example environmental conditions include microgravity for small-body missions, high temperature and pressure (460 °C, 93bar) on Venus, and at Europa the radiation environment is estimated at 2.9 Mrad total ionizing dose (TID) behind 100 mil thick aluminum.

Contamination control and planetary protection are important considerations for sample acquisition and handling technologies. Contamination may include Earth-source contaminants produced by the sampling tool, handling system, or deposited on the sampling location from another source on the rover. "Cleaning to sterility" technologies are needed that will be compatible with spacecraft materials and processes. Surface cleaning validation methods are needed that can be used routinely to quantify trace amounts (~ng/cm<sup>2</sup>) of organic contamination and submicron particle (~100nm size) contamination. Priority will be given to cleaning and sterilization methods that have potential for in-situ applications.

Component technologies for low-mass and low-power systems tolerant to the in-situ environment are of particular

---

interest. Technical feasibility should be demonstrated during Phase I and a full capability unit of at least TRL 4 should be delivered in Phase II. Proposals should show an understanding of relevant science needs and engineering constraints and present a feasible plan to fully develop a technology and infuse it into a NASA program. Specific areas of interest include the following:

- Six-axis force-torque sensors for 100g and 35kg payloads.
- Steep terrain adherence.
- Tether play-out and retrieval systems including tension and length sensing.
- Low-mass tether cables with power and communication.
- Sampling system deployment mechanisms.
- Low mass/power vision systems and processing capabilities that enable faster surface traverse.
- Modular actuators and actuators for harsh environments.
- Abrading bit providing smooth surface preparation.
- Small body sampling tool.
- Cleaning to sterility technologies that will be compatible with spacecraft materials and processes.
- Surface cleaning validation technology to quantify trace amount ( $\sim\text{ng}/\text{cm}^2$ ) of organic contamination and submicron particle ( $\sim 100\text{nm}$  size) contamination.
- Sample handling technologies that minimize cross contamination and preserve mechanical integrity of samples.