

## DPA26TZ01-NV001

### Medical Swarm Robotics for Extraction and Life-Saving Interventions Frequently Asked Questions (FAQs)

1. How broadly is DARPA interpreting “swarm-capable” and “self-linking” for this topic?

**Answer:**

- **Swarm-Capable: multiple, ideally identical, agents communicate and coordinate to accomplish a task**
- **Self-Linking: multiple, ideally identical, agents physically interlock to create a new shape for the purpose of completing a task.**
- **In this topic we would be seeking completion of the tasks of moving casualties, stabilizing limbs, delivering medication, controlling hemorrhage.**

2. Would DARPA view a heterogeneous architecture, where mobility/traversal and intervention capabilities are separated across cooperating robotic elements, as fully responsive to the topic?

**A: The intended goal would be homogenous design, such that one lost element would not be missed or degrade capability.**

3. For extraction, is DARPA primarily interested in full autonomous short-distance casualty movement, or would systems focused on repositioning, dragging, or assisting transfer onto a SKED/litter also be considered strongly responsive in Phase I?

**A: DARPA is interested in the ability to move casualties to safety without risking additional human life – solutions that facilitate this through safe patient movement (lifting or dragging a casualty) or that enable movement of a casualty by other systems by placing a casualty onto a litter/SKED would be responsive.**

4. How should proposers treat the IFAK-sized / drone-deployable language in Phase I: as a firm design constraint, or more as a directional objective?

**A: Size and weight requirements may be flexible but need to be designed to be carried via a drone or deployable in a soldier’s kit or both. The objective is to self assemble from available units that are born or brought to remote locations by warfighter or autonomous systems. Optimize small size and big capability is the target.**