DARPA-BAA-10-65: Maximum Mobility and Manipulation (M3)

<table>
<thead>
<tr>
<th>Letter of Intent to Agency</th>
<th>No</th>
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<tbody>
<tr>
<td>Proposal to Sponsored Programs</td>
<td>07/12/2010</td>
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<tr>
<td>Submission to Agency</td>
<td>07/19/2010 4 PM ET</td>
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<tr>
<th>Estimated Total Funding</th>
<th>TBD</th>
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<tr>
<td>Anticipated No. of Awards</td>
<td>Multiple</td>
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<tr>
<td>Cost Share</td>
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Link to Opportunity | Here |

The Defense Sciences Office (DSO), Defense Advanced Research Projects Agency (DARPA), U.S. Department of Defense, is soliciting research proposals in the area of ground robot mobility and manipulation. The Maximum Mobility and Manipulation (M3) program is designed to create and demonstrate significant advances in both science and engineering for ground robots. In particular:

- M3 strives to create a significantly improved scientific framework for understanding robot mobility and manipulation in natural environments
- M3 strives to significantly improve robot capabilities through fundamentally new approaches to the engineering of better design tools, fabrication methods, and control algorithms

To meet M3’s science and engineering goals proposals to M3 should include both scientific and engineering efforts, and specifically include modeling/analysis, simulation, and experiment.
Proposers are strongly encouraged to submit a proposal abstract in advance of a full proposal. Abstracts are due June 14th, 2010 by 4 PM ET. Proposal abstracts are to be submitted through the Sponsored Programs Office. DARPA will respond to proposal abstracts with a statement as to whether DARPA is interested in the idea. Regardless of DARPA's response to a proposal abstract, proposers may submit a full proposal.

To find more opportunities from this agency, please see here.

For detailed information about this opportunity please see the full solicitation. Please contact Sponsored Programs (4-5066) with questions regarding proposal submission requirements.

If you have any questions regarding this announcement, please contact:

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