A11 for Off-Earth Construction — Autonomous Base Building

Aleksej Dvojnev

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Author: Aleksej Dvojnev

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Annotation

This document presents an autonomous construction framework for off-Earth environments, including lunar and Martian surface operations.

The framework provides a structured, scalable, and communication-efficient method for coordinating heterogeneous robotic agents performing construction tasks under extreme environmental constraints.

The model addresses key challenges in extraterrestrial construction: limited communication, high latency, hazardous terrain, resource scarcity, and the need for predictable, certifiable behavior.

The approach is based on structured decision-making principles derived from the A11 cognitive architecture.

Contents

1. Introduction

Off-Earth construction is a critical capability for:

- lunar bases
- Martian habitats
- autonomous mining stations
- scientific outposts
- long-duration missions

Human presence is limited by:

- communication delays
- radiation
- dust hazards
- extreme temperatures
- resource constraints

Therefore, construction must be performed by **autonomous multi-robot systems** capable of:

- coordination
- conflict resolution
- resource allocation
- task execution
- adaptation to environmental uncertainty

This document introduces a structured framework for autonomous base building in off-Earth environments.

2. Problem Definition

Off-Earth construction requires:

- multiple autonomous robots
- operating in hazardous, unstructured terrain
- with limited communication

- performing interdependent tasks
- using local resources (ISRU)

The system must ensure:

- safety
- predictable coordination
- efficient resource usage
- robustness to failures
- minimal reliance on Earth-based control

3. Challenges of Off-Earth Construction

3.1 Communication Delays

Earth–Moon: ~1.3 seconds

Earth–Mars: 4–24 minutes

→ Real-time teleoperation is impossible.

3.2 Harsh Environment

- dust storms
- regolith instability
- radiation
- extreme temperature swings

3.3 Resource Constraints

- limited energy
- limited materials
- limited mobility

3.4 Multi-Agent Dependencies

Construction tasks require:

- sequencing
- coordination

- shared workspace management

3.5 Safety and Certifiability

Systems must be:

- deterministic
- interpretable
- failure-tolerant

4. A11-Based Construction Framework

The framework uses a structured decision-making loop with:

- contextual interpretation
- option generation
- constraint filtering
- priority assignment
- action selection

This ensures:

- predictable coordination
- safe task execution
- scalable multi-agent behavior
- minimal communication requirements

5. System Architecture

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┌──────────────────────────────────────────────┐
│   Perception & Terrain Mapping          │
└──────────────────────────────────────────────┘
        │
        ▼
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┌──────────────────────────────────────────────┐
│   Task & Resource Situation Analysis   │
└──────────────────────────────────────────────┘
        │
        ▼
┌──────────────────────────────────────────────┐
│ A11 Off-Earth Construction Module        │
│  • Context Interpretation                │
│  • Task Option Generation                │
│  • Constraint Filtering                  │
│  • Priority Assignment                   │
│  • Action Selection                      │
└──────────────────────────────────────────────┘
        │
        ▼
┌──────────────────────────────────────────────┐
│      Motion Planning                     │
└──────────────────────────────────────────────┘
        │
        ▼
┌──────────────────────────────────────────────┐
│         Control                          │
└──────────────────────────────────────────────┘
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6. Multi-Agent Construction Algorithm

Step 1 — Context Interpretation

Each robot evaluates:

- terrain
- obstacles
- nearby agents
- resource availability
- task dependencies

Step 2 — Task Option Generation

Robots generate feasible actions:

- excavation
- transport
- deposition
- assembly
- inspection
- relocation

Step 3 — Constraint Filtering

Options are filtered based on:

- terrain stability
- energy availability
- collision risk
- task sequencing
- structural integrity requirements

Step 4 — Priority Assignment

Priority is assigned using:

- minimal-risk principle
- minimal-delay principle
- dependency-resolution rule
- deadlock-avoidance rule

Step 5 — Action Selection

Each robot selects the action with:

- highest safety score
- highest contribution to construction progress
- lowest energy cost

7. Resource Utilization (ISRU) Integration

The framework supports ISRU-based workflows:

- regolith excavation
- material transport
- additive manufacturing
- structural assembly

Robots coordinate to:

- maintain material flow
- avoid bottlenecks
- optimize energy usage
- ensure structural stability

8. Example Scenarios

Scenario A — Lunar Habitat Foundation

Robots must:

- clear terrain
- level surface
- deposit regolith layers

Outcome:

- conflict-free coordination
- stable sequencing

- predictable progress

Scenario B — Martian Base Assembly

Robots assemble modular components.

Outcome:

- dependency-aware task execution
- safe workspace sharing
- minimal communication required

Scenario C — ISRU Material Pipeline

Excavators, haulers, and printers operate together.

Outcome:

- stable material flow
- no deadlocks
- energy-efficient behavior

9. Safety and Reliability Considerations

The framework ensures:

- deterministic decision-making
- bounded decision time
- fallback to safe stop
- robustness to sensor noise
- resilience to partial failures

It is suitable for safety-critical certification.

10. Performance Characteristics

- low computational cost
- scalable to large robot teams
- robust to communication loss

- compatible with heterogeneous robots
- predictable convergence

11. Extensions

Future extensions include:

- cooperative structure design
- swarm-level optimization
- integration with orbital assets
- autonomous repair and maintenance

12. Conclusion

This document presents a structured framework for autonomous off-Earth construction.

It enables predictable, scalable, and communication-efficient coordination among heterogeneous robotic agents performing construction tasks in extreme environments.

The framework is based on principles derived from the A11 cognitive architecture.

13. References

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