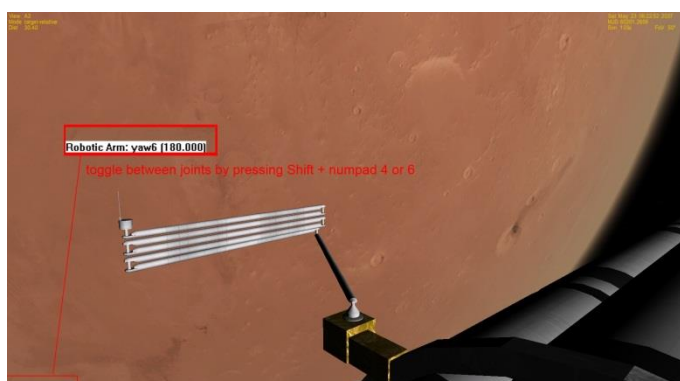
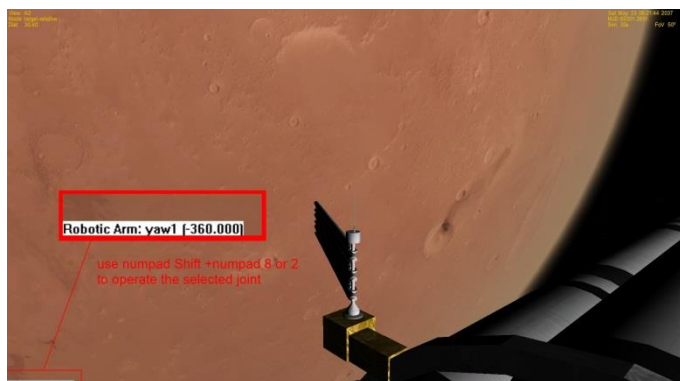
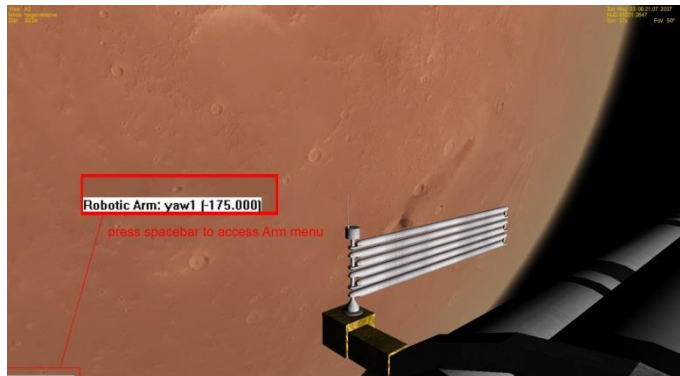


Robotic arm

Pegasus has two robotic arms. These arms are used for multiple tasks, such as refuelling, or EVA. To operate the robotic arms, press f3 and select either A1 or A2. Once you have selected the desired robotic arm, press spacebar to access the arm operation plane (see below), and press Shift + numpad 2 or 8 to operate the selected joint. To toggle between joints press Shift + numpad 4 or 6.



Grappling objects with the robotic arm

The robotic arm has an attachment point at the tip of the end joint. This point can be used to grapple objects such as the refuelling tank. To attach an object, simply move the arm so that the tip is where the attachment point on the object is, then press A to

access the attachment info plane and toggle through the two attachment points by pressing Shift + numpad 4 or 6 until you find the 'Attach' option, do NOT use the 'rms' option, because that is the point used to keep the arm attached to Pegasus. To grapple or release the object press Shift + numpad 0.

