MAGIK

HTV-X1 OVERVIEW IMAGES	
MAGIK AI	AI-4395
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To	JAXA
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ABSTRACT

The Manipulator Analysis Graphics and Interactive Kinematics (MAGIK) Robotic Analysis Team has completed an action to publish overview images of Flight HTV-X1 Extravehicular Robotics (EVR) operations. These images were originally published in MAGIK AI-4179 HTV-X1 Launch Minus 6 (L-6) months EVR Choreography.

The Flight HTV-X1 manifest includes the delivery of the Intravehicular Activity (IVA) Resuppliable Small Exposed Experiment Platform (i-SEEP) 3B payload. The i-SEEP-3B payload will be extracted robotically from the HTV-X1 vehicle by the Space Station Remote Manipulator System (SSRMS) and Special Purpose Dexterous Manipulator (SPDM) before handoff to the Japanese Experiment Module (JEM) Robotic Manipulator System (RMS) to bring i-SEEP-3B internal via the JEM Airlock (JEMAL). Once integrated with payloads, i-SEEP-3B will be installed on the JEM Exposed Facility (JEM-EF) for future operations at Site 5.

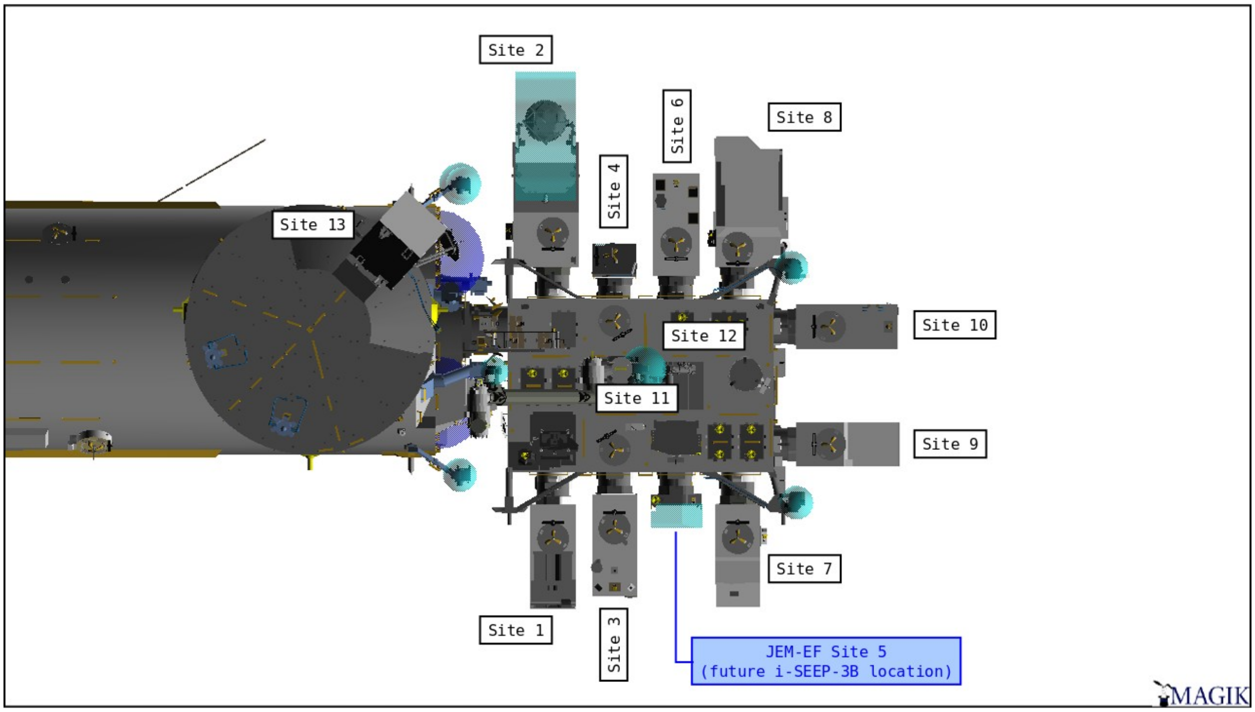

Figure 1: JEM-EF Site Overview
Orthographic View Looking ISS Nadir

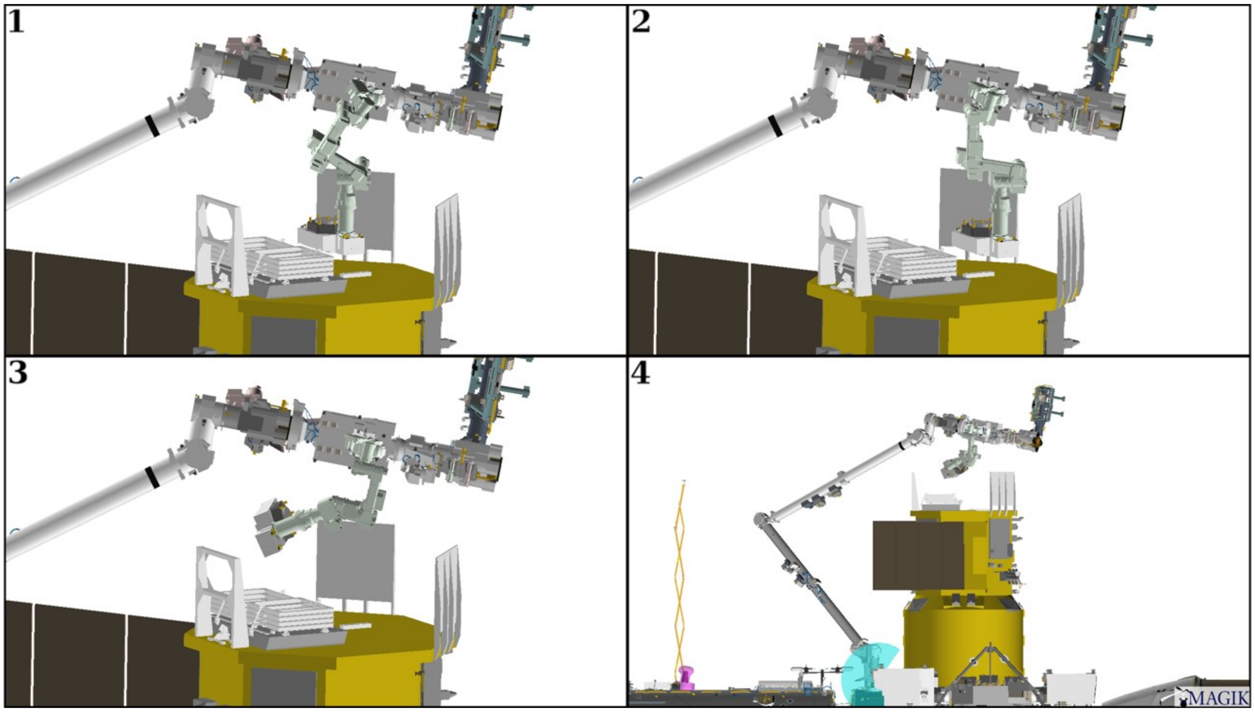

Figure 2: i-SEEP-3B Extraction from HTV-X1 by SSRMS/SPDM
Isometric View Looking ISS Forward-Starboard-Zenith

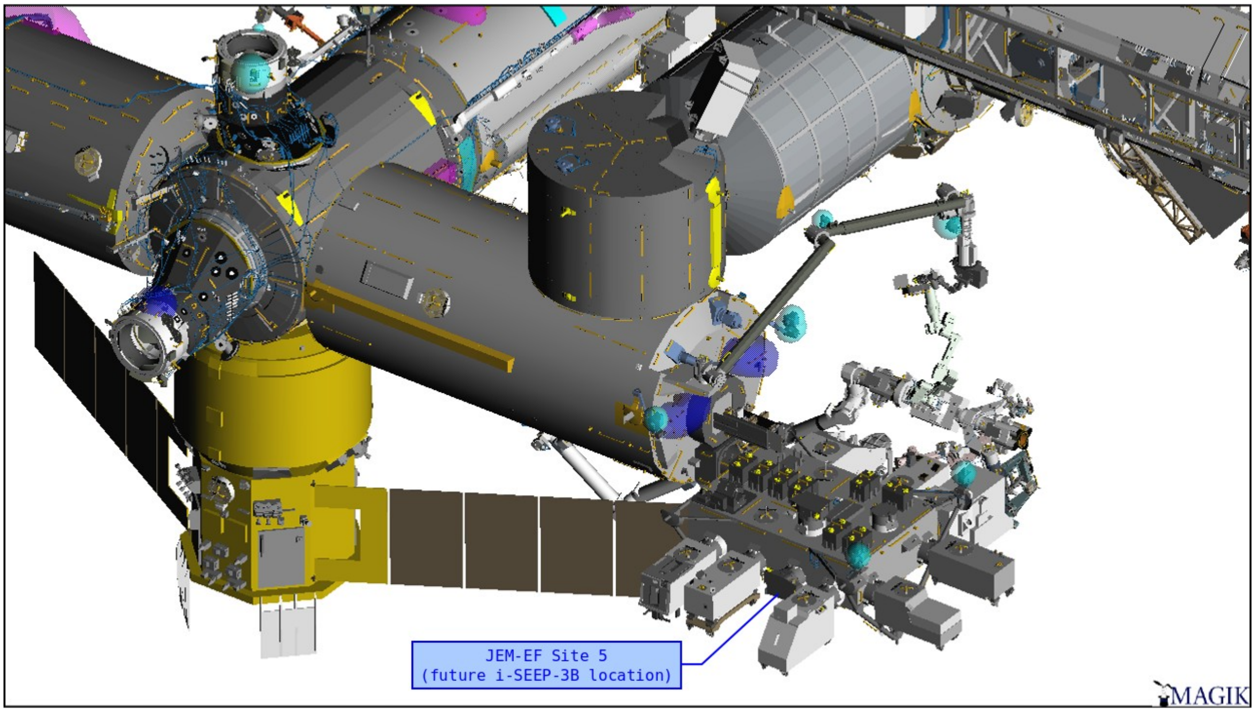

Figure 3: i-SEEP-3B Handoff from SSRMS/SPDM to JEM RMS
Isometric View Looking ISS Starboard-Aft-Nadir