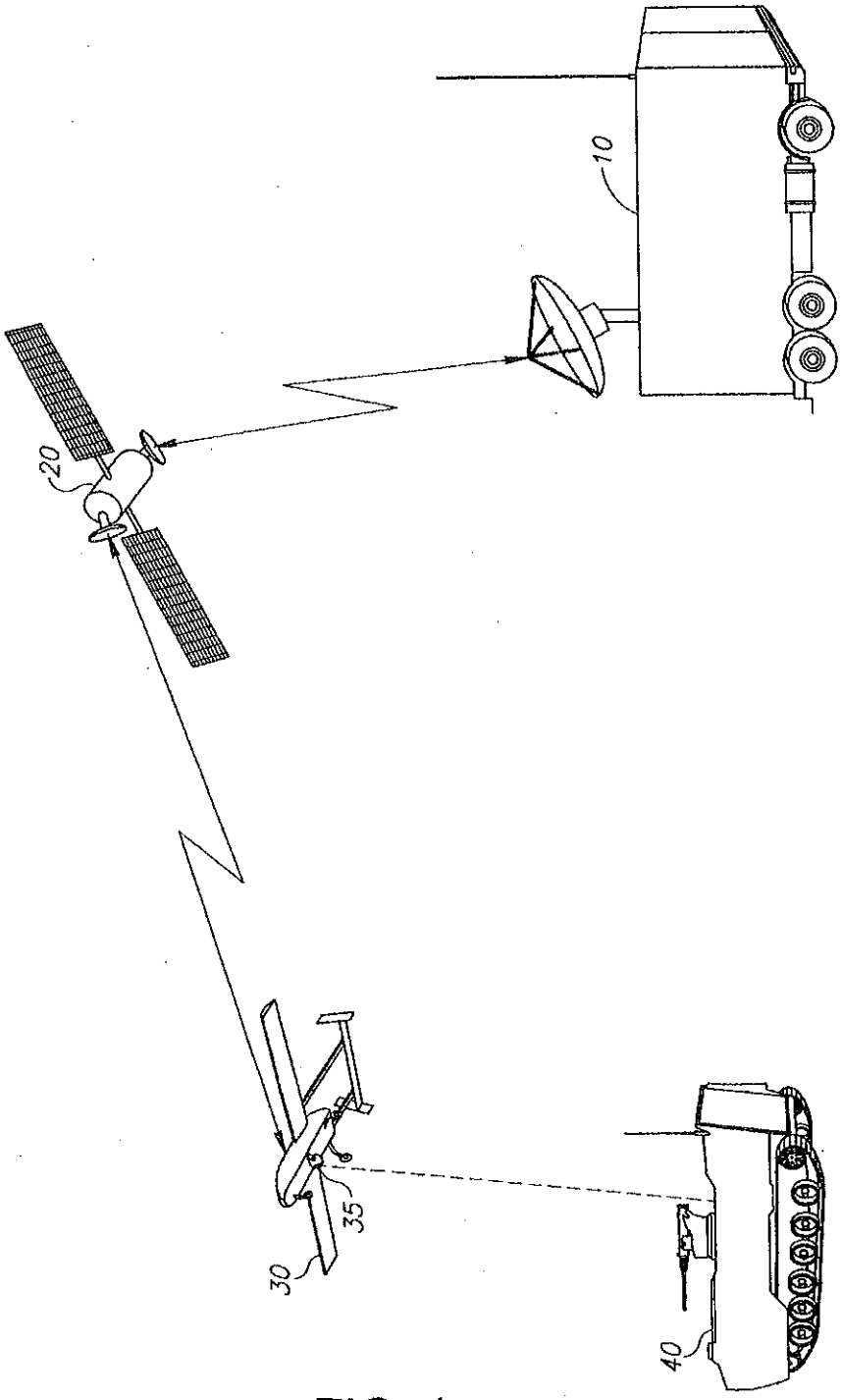


FIG. 1
(Existing Art)

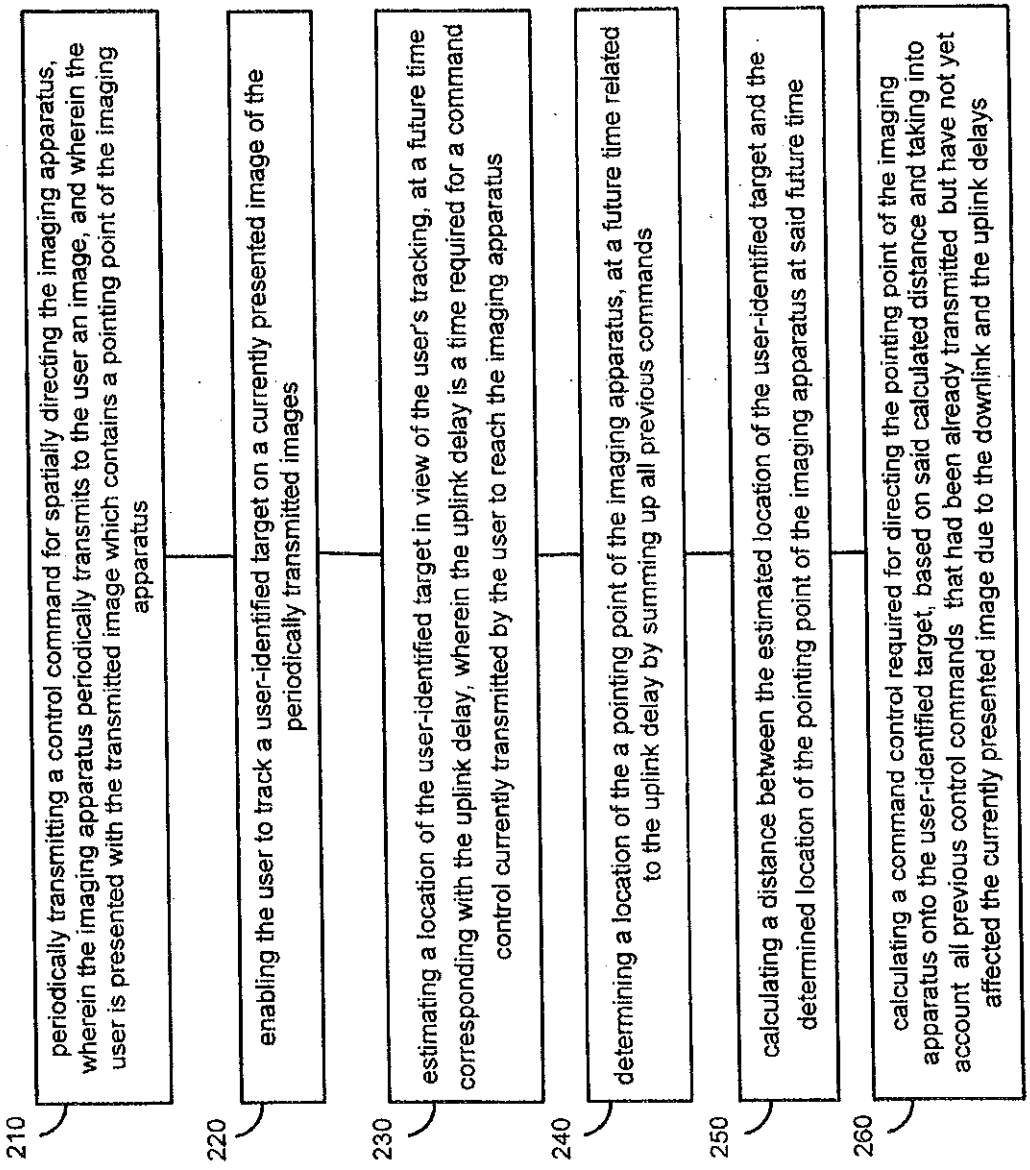

210
periodically transmitting a control command for spatially directing the imaging apparatus, wherein the imaging apparatus periodically transmits to the user an image, and wherein the user is presented with the transmitted image which contains a pointing point of the imaging apparatus
220
enabling the user to track a user-identified target on a currently presented image of the periodically transmitted images
230
estimating a location of the user-identified target in view of the user's tracking, at a future time corresponding with the uplink delay, wherein the uplink delay is a time required for a command control currently transmitted by the user to reach the imaging apparatus
240
determining a location of the a pointing point of the imaging apparatus, at a future time related to the uplink delay by summing up all previous commands
250
calculating a distance between the estimated location of the user-identified target and the determined location of the pointing point of the imaging apparatus at said future time
260
calculating a command control required for directing the pointing point of the imaging apparatus onto the user-identified target, based on said calculated distance and taking into account all previous control commands that had been already transmitted but have not yet affected the currently presented image due to the downlink and the uplink delays

FIG. 2

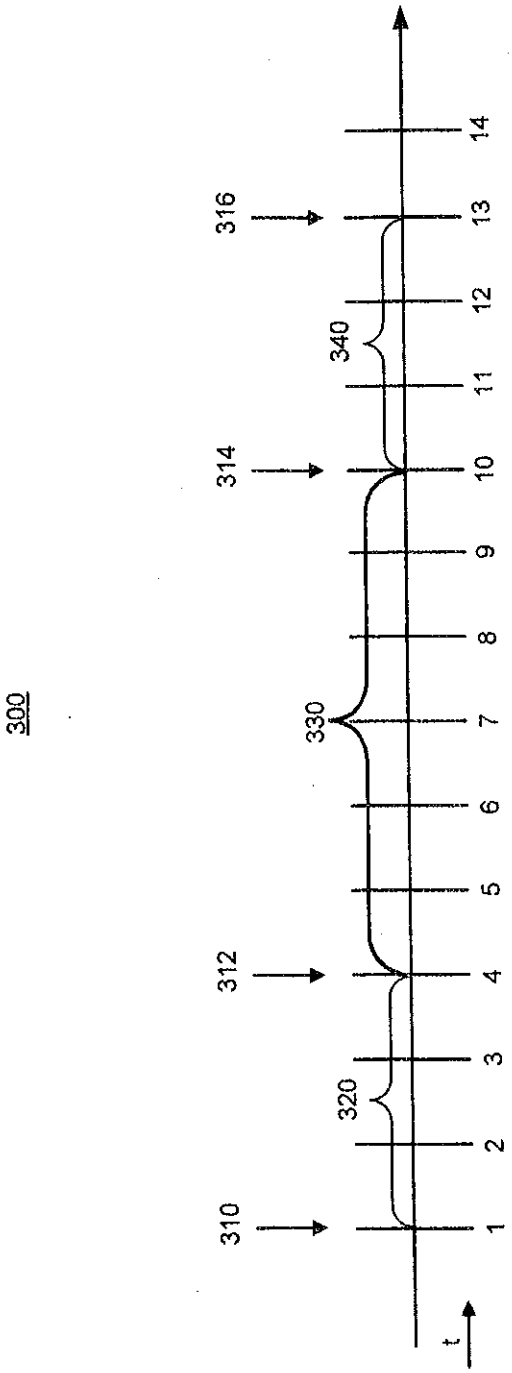


FIG. 3

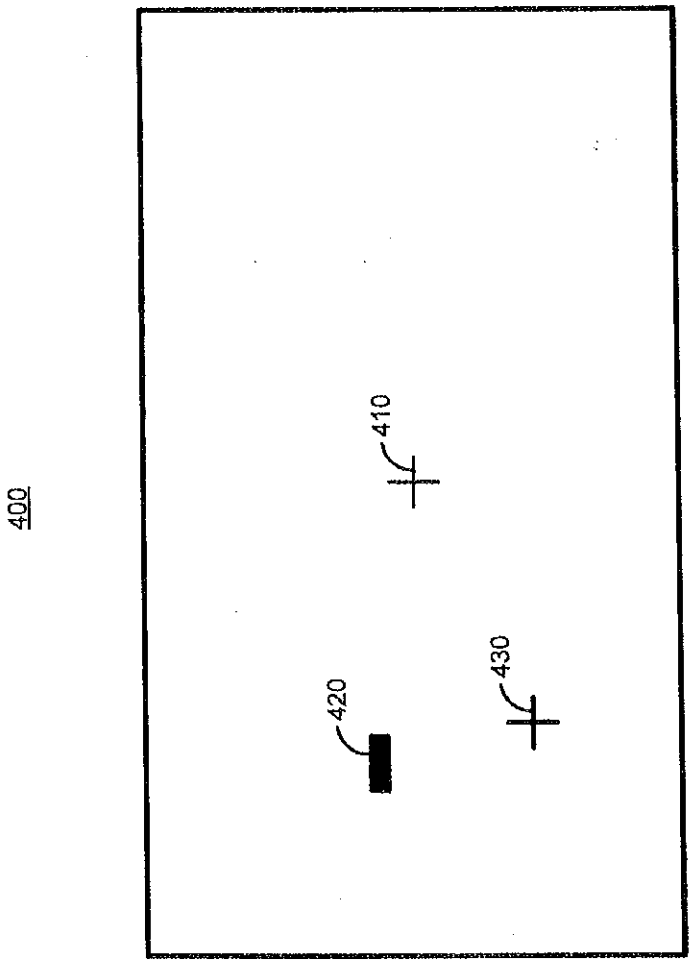


FIG. 4

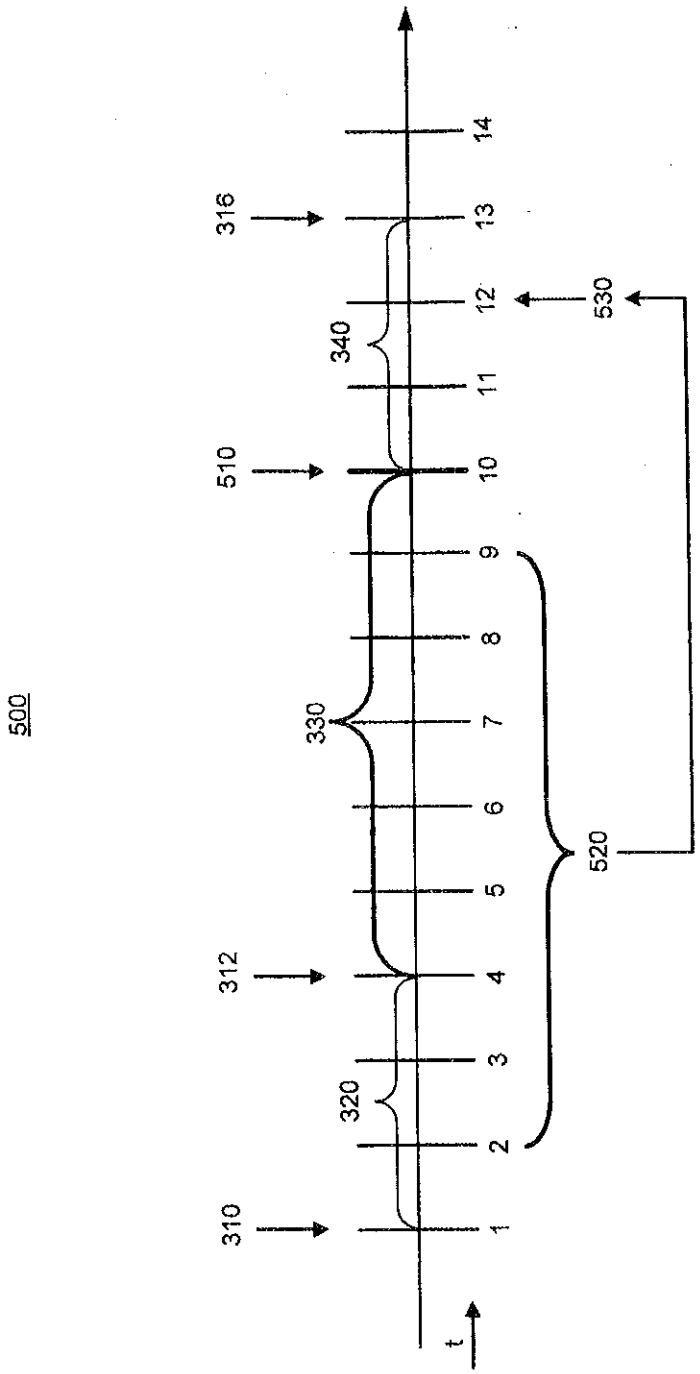

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FIG. 5

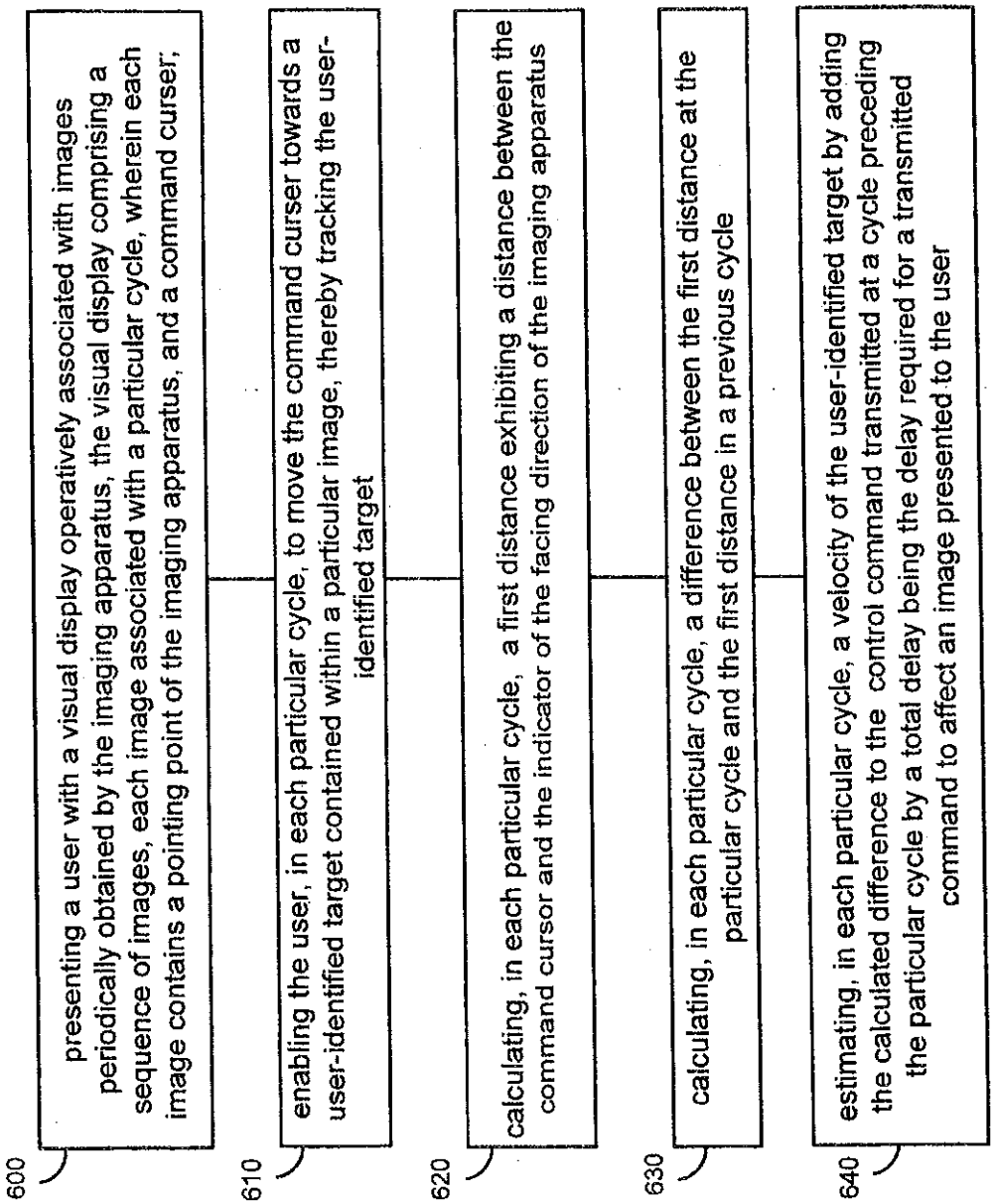

600
presenting a user with a visual display operatively associated with images periodically obtained by the imaging apparatus, the visual display comprising a sequence of images, each image associated with a particular cycle, wherein each image contains a pointing point of the imaging apparatus, and a command curser;
610
enabling the user, in each particular cycle, to move the command curser towards a user-identified target contained within a particular image, thereby tracking the user-identified target
620
calculating, in each particular cycle, a first distance exhibiting a distance between the command cursor and the indicator of the facing direction of the imaging apparatus
630
calculating, in each particular cycle, a difference between the first distance at the particular cycle and the first distance in a previous cycle
640
estimating, in each particular cycle, a velocity of the user-identified target by adding the calculated difference to the control command transmitted at a cycle preceding the particular cycle by a total delay being the delay required for a transmitted command to affect an image presented to the user

FIG. 6

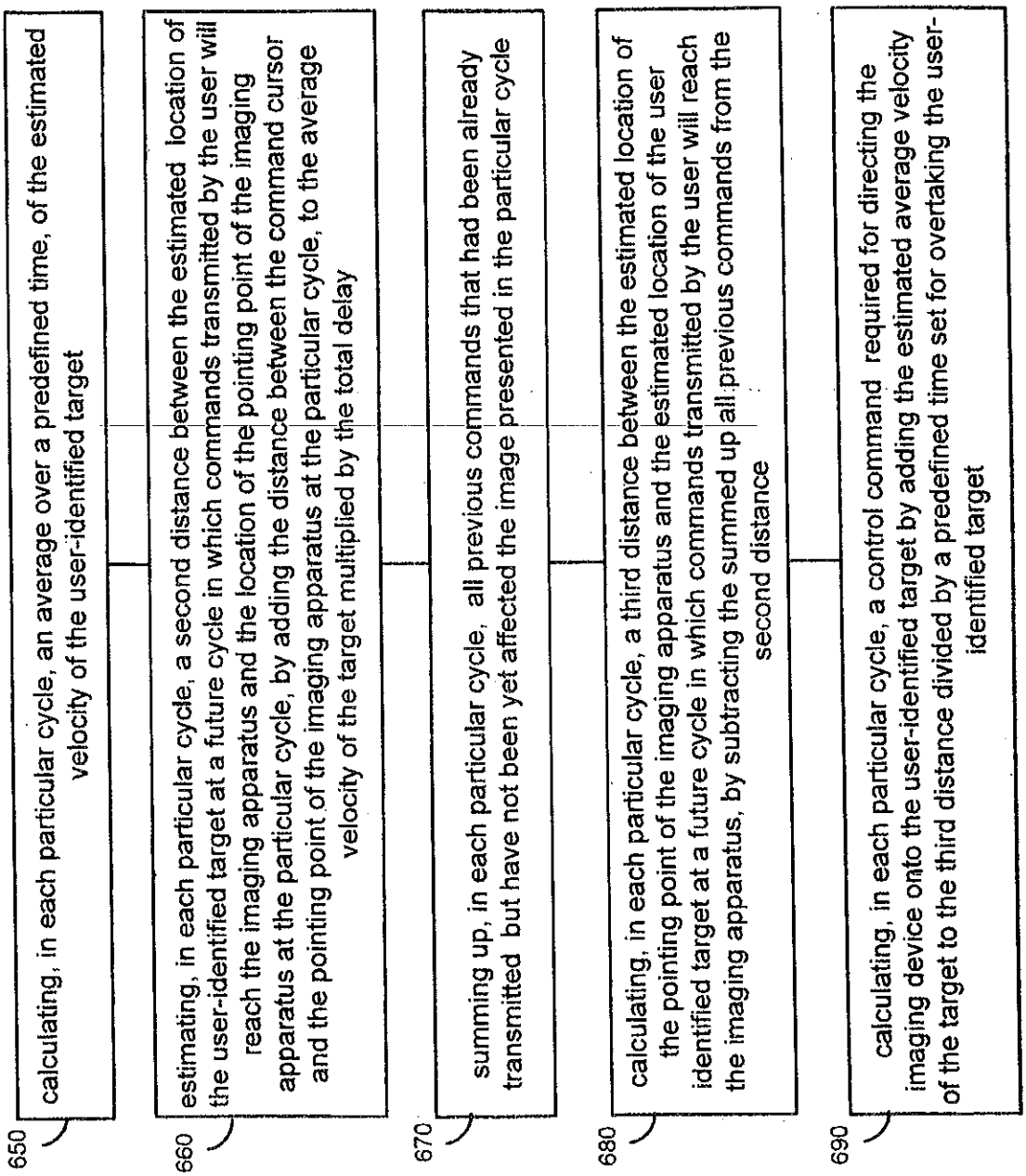

650
calculating, in each particular cycle, an average over a predefined time, of the estimated velocity of the user-identified target
660
estimating, in each particular cycle, a second distance between the estimated location of the user-identified target at a future cycle in which commands transmitted by the user will reach the imaging apparatus and the location of the pointing point of the imaging apparatus at the particular cycle, by adding the distance between the command cursor and the pointing point of the imaging apparatus at the particular cycle, to the average velocity of the target multiplied by the total delay
670
summing up, in each particular cycle, all previous commands that had been already transmitted but have not been yet affected the image presented in the particular cycle
680
calculating, in each particular cycle, a third distance between the estimated location of the pointing point of the imaging apparatus and the estimated location of the user identified target at a future cycle in which commands transmitted by the user will reach the imaging apparatus, by subtracting the summed up all previous commands from the second distance
690
calculating, in each particular cycle, a control command required for directing the imaging device onto the user-identified target by adding the estimated average velocity of the target to the third distance divided by a predefined time set for overtaking the user-identified target

FIG. 7