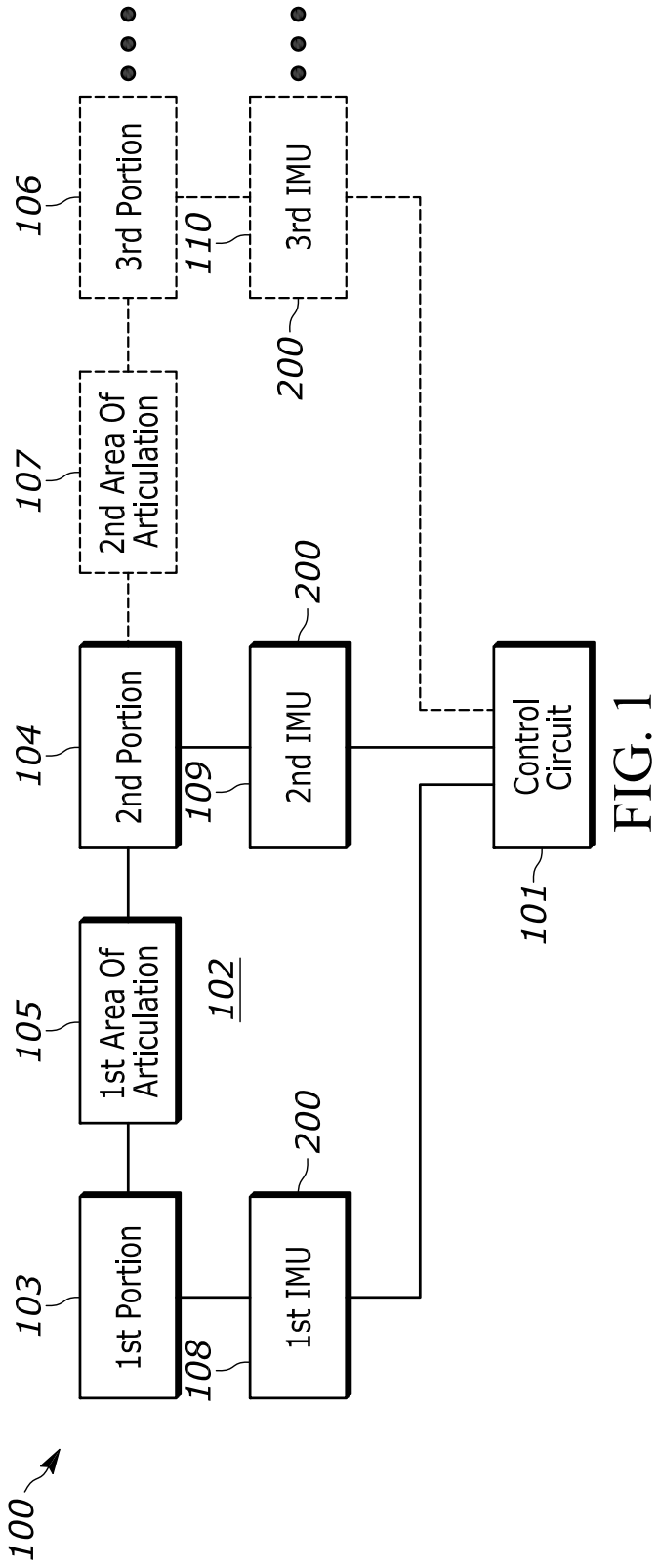

100
103
1st Portion
108
1st IMU
200
105
1st Area Of Articulation
102
104
2nd Portion
109
2nd IMU
200
107
2nd Area Of Articulation
106
3rd Portion
110
3rd IMU
200
101
Control Circuit

FIG. 1

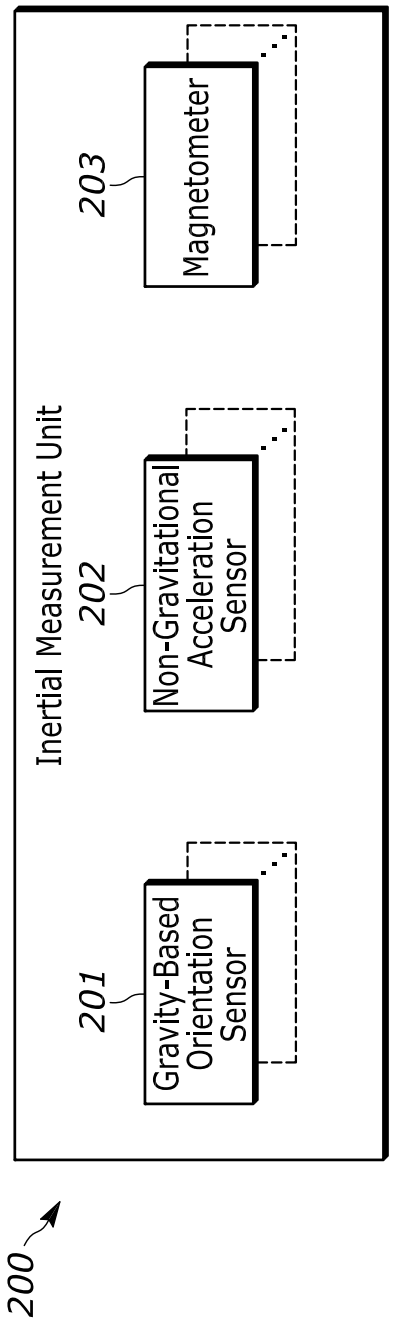

200
Inertial Measurement Unit
201
Gravity-Based Orientation Sensor
202
Non-Gravitational Acceleration Sensor
203
Magnetometer

FIG. 2

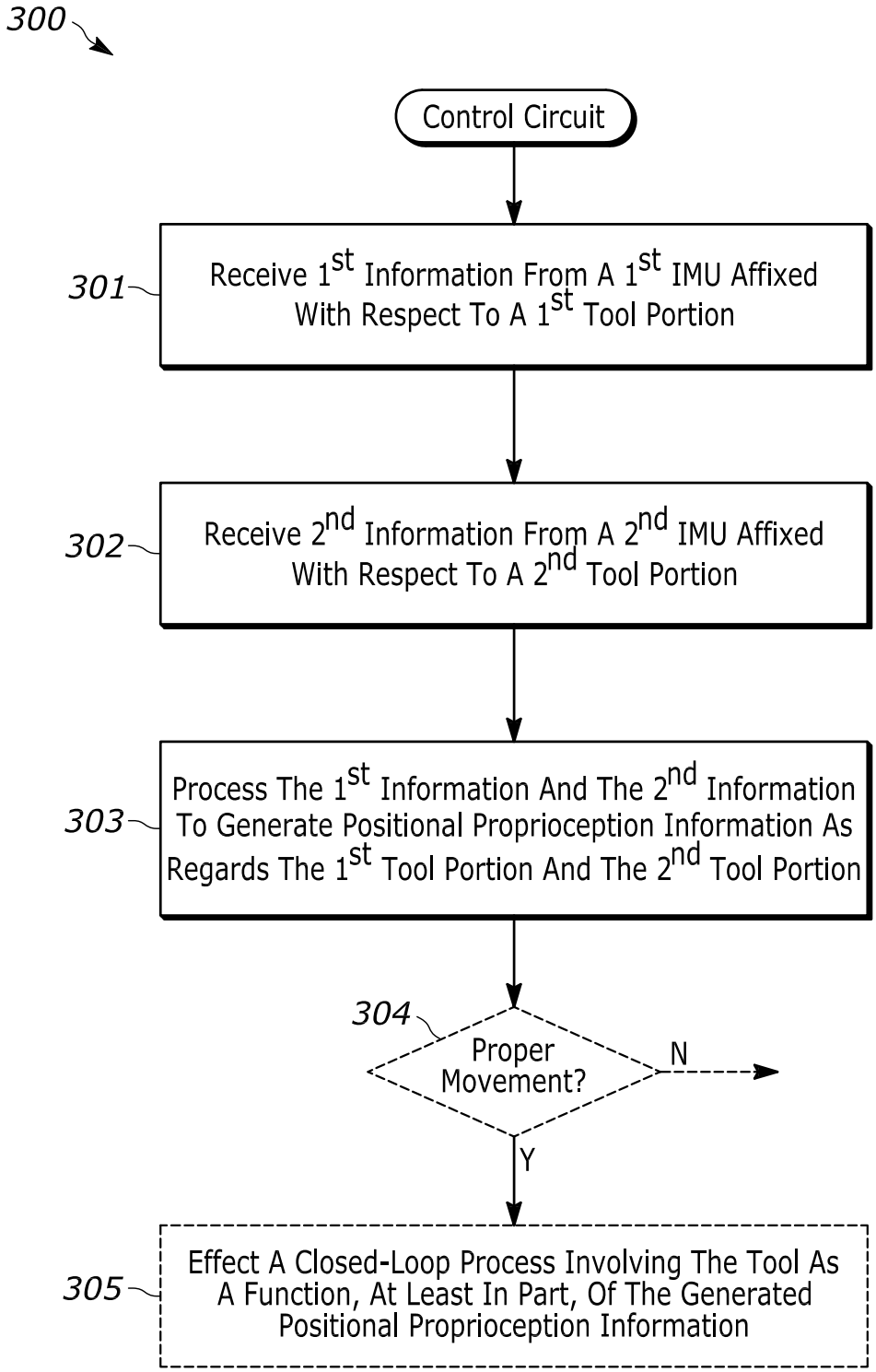

300
Control Circuit
301
Receive 1st Information From A 1st IMU Affixed With Respect To A 1st Tool Portion
302
Receive 2nd Information From A 2nd IMU Affixed With Respect To A 2nd Tool Portion
303
Process The 1st Information And The 2nd Information To Generate Positional Proprioception Information As Regards The 1st Tool Portion And The 2nd Tool Portion
304
Proper Movement?
N
Y
305
Effect A Closed-Loop Process Involving The Tool As A Function, At Least In Part, Of The Generated Positional Proprioception Information

FIG. 3

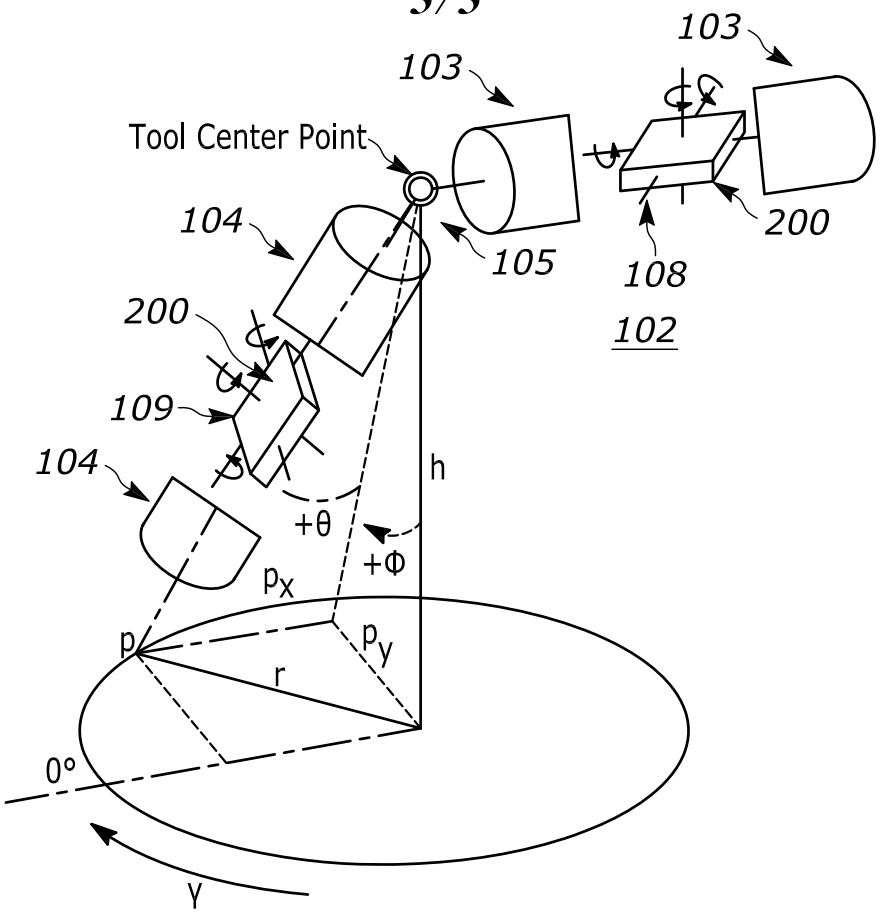

103
103
Tool Center Point
104
105
108
200
102
200
109
104
h
+θ
+Φ
px
p
py
r
0°
γ

FIG. 4

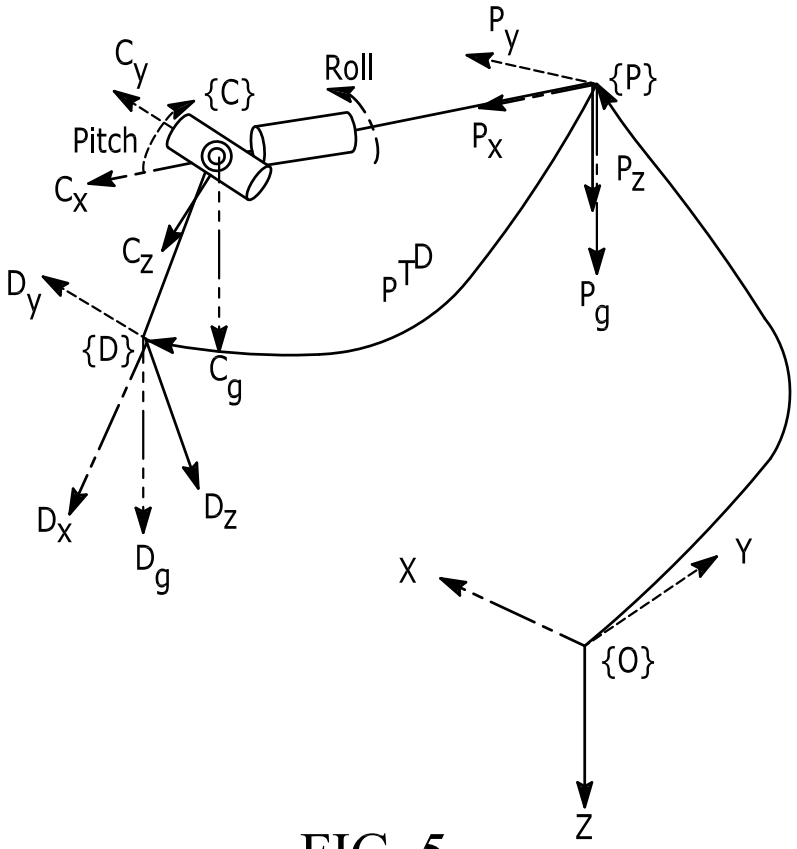

Py
Cy
{C}
Roll
{P}
Pitch
Px
Pz
Cx
Cz
PTD
Dy
Pg
{D}
Cg
Dx
Dz
Dg
X
Y
{O}
Z

FIG. 5