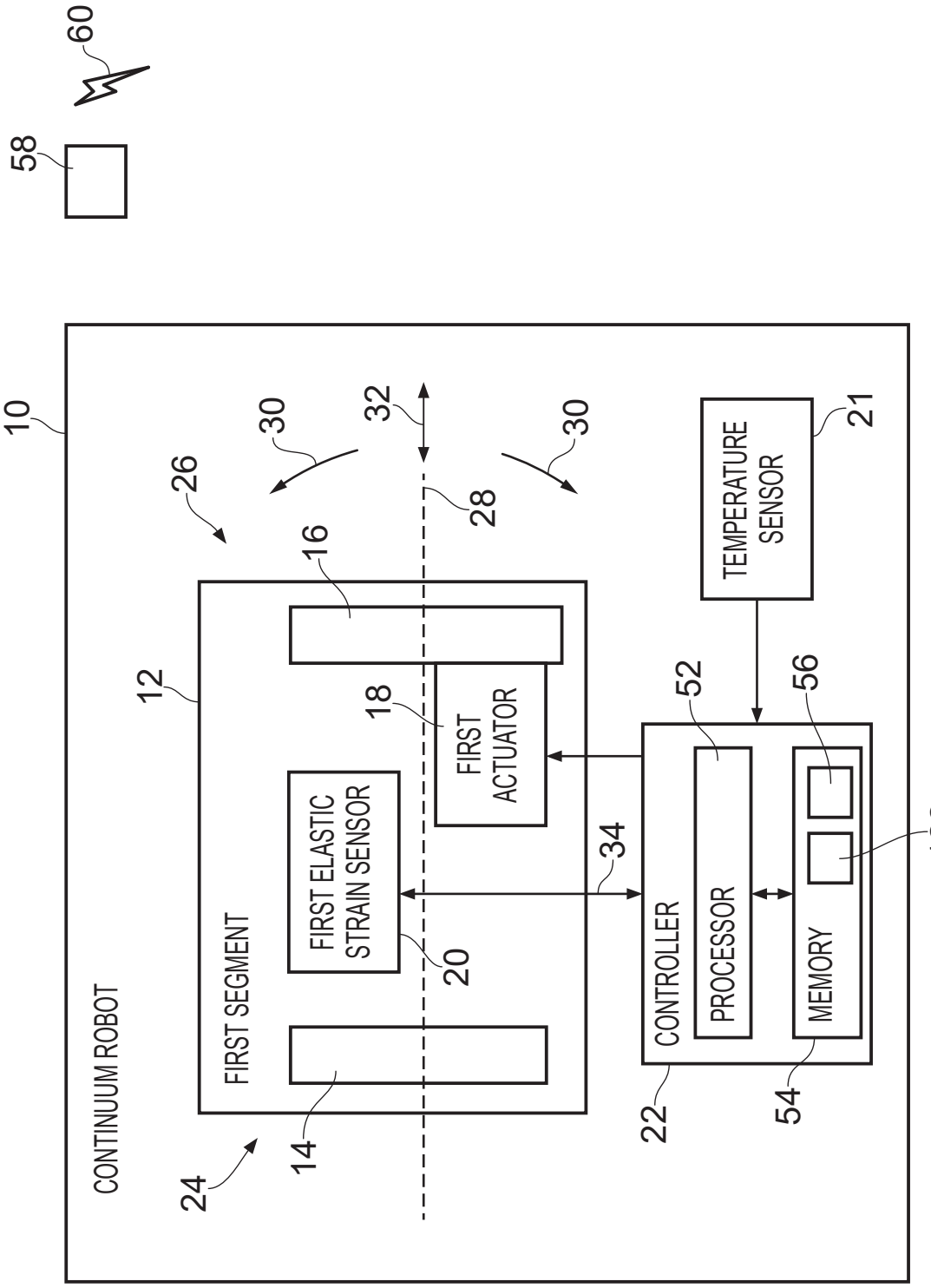

60
58
10
CONTINUUM ROBOT
FIRST SEGMENT
12
16
18
FIRST ACTUATOR
FIRST ELASTIC STRAIN SENSOR
20
14
24
26
30
32
28
30
34
TEMPERATURE SENSOR
21
CONTROLLER
52
PROCESSOR
56
MEMORY
122
22
54

FIG. 1

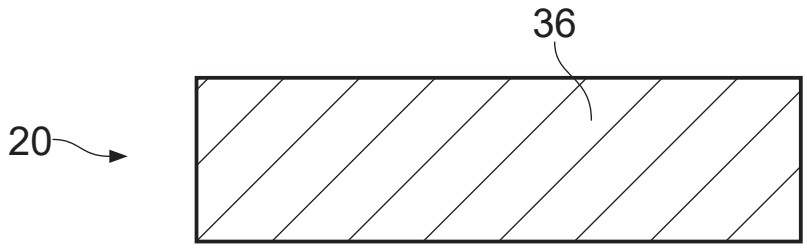


FIG. 2

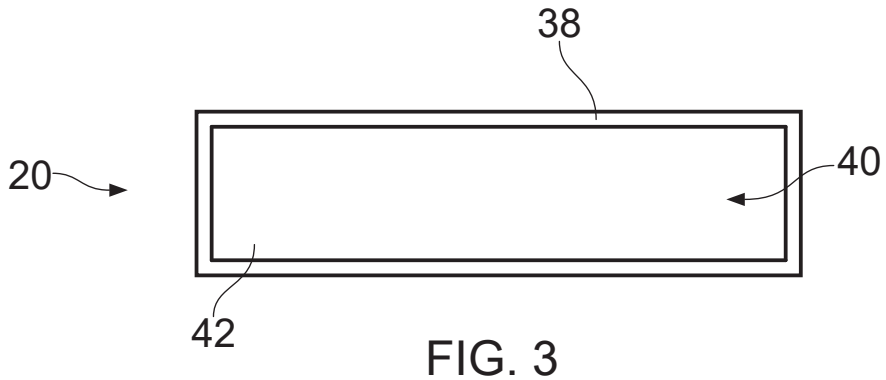


FIG. 3

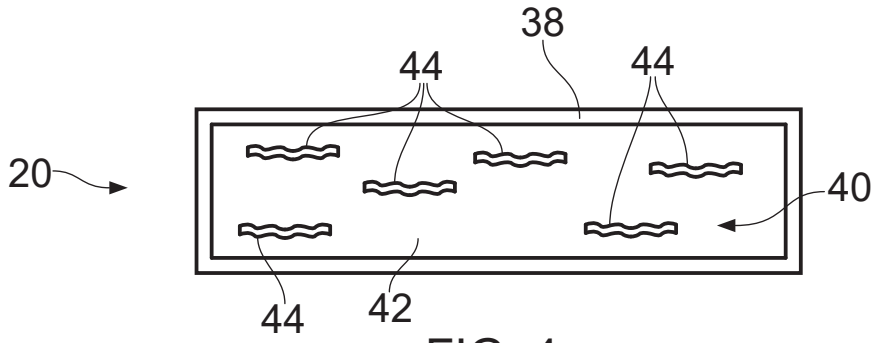


FIG. 4

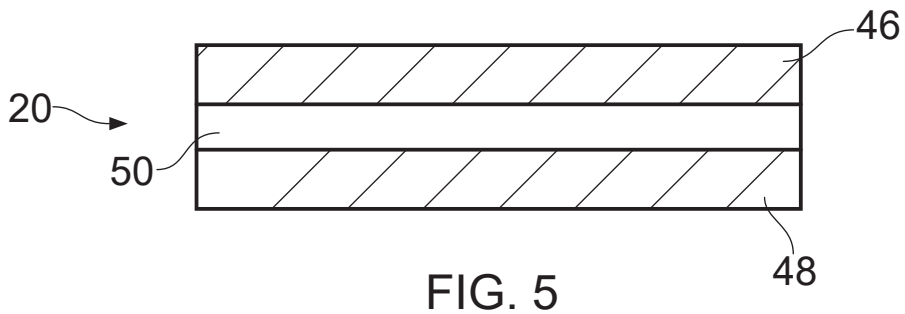


FIG. 5

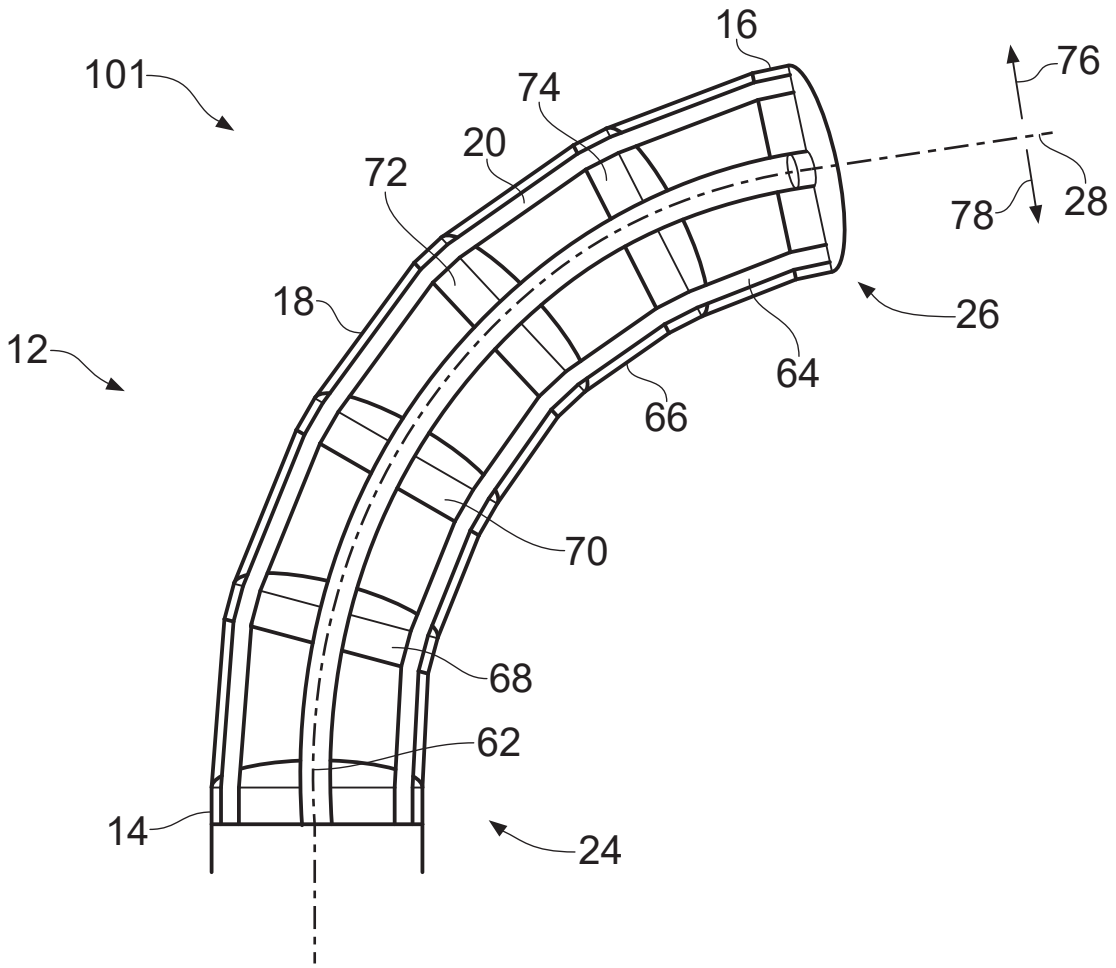


FIG. 6

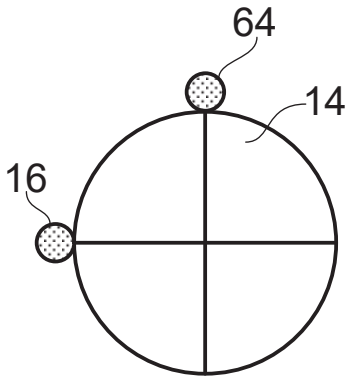


FIG. 7A

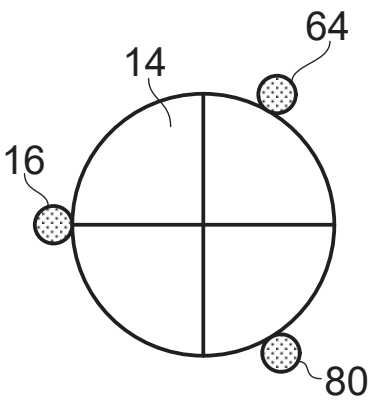


FIG. 7B

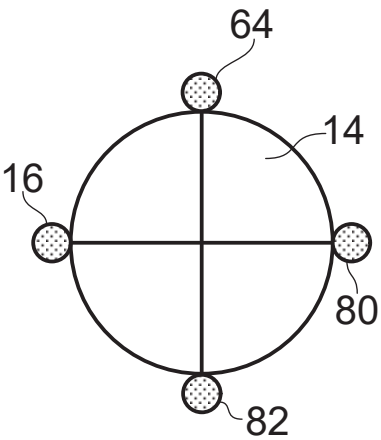


FIG. 7C

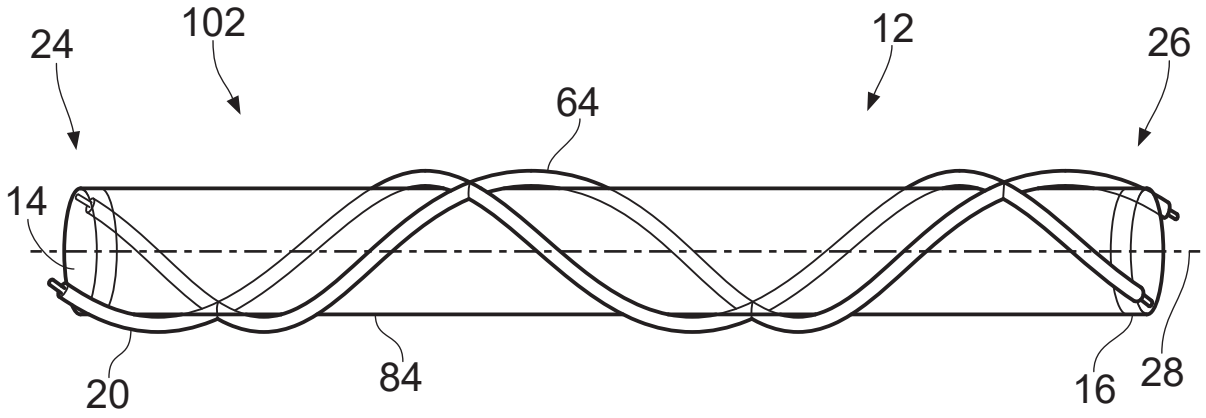

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FIG. 8

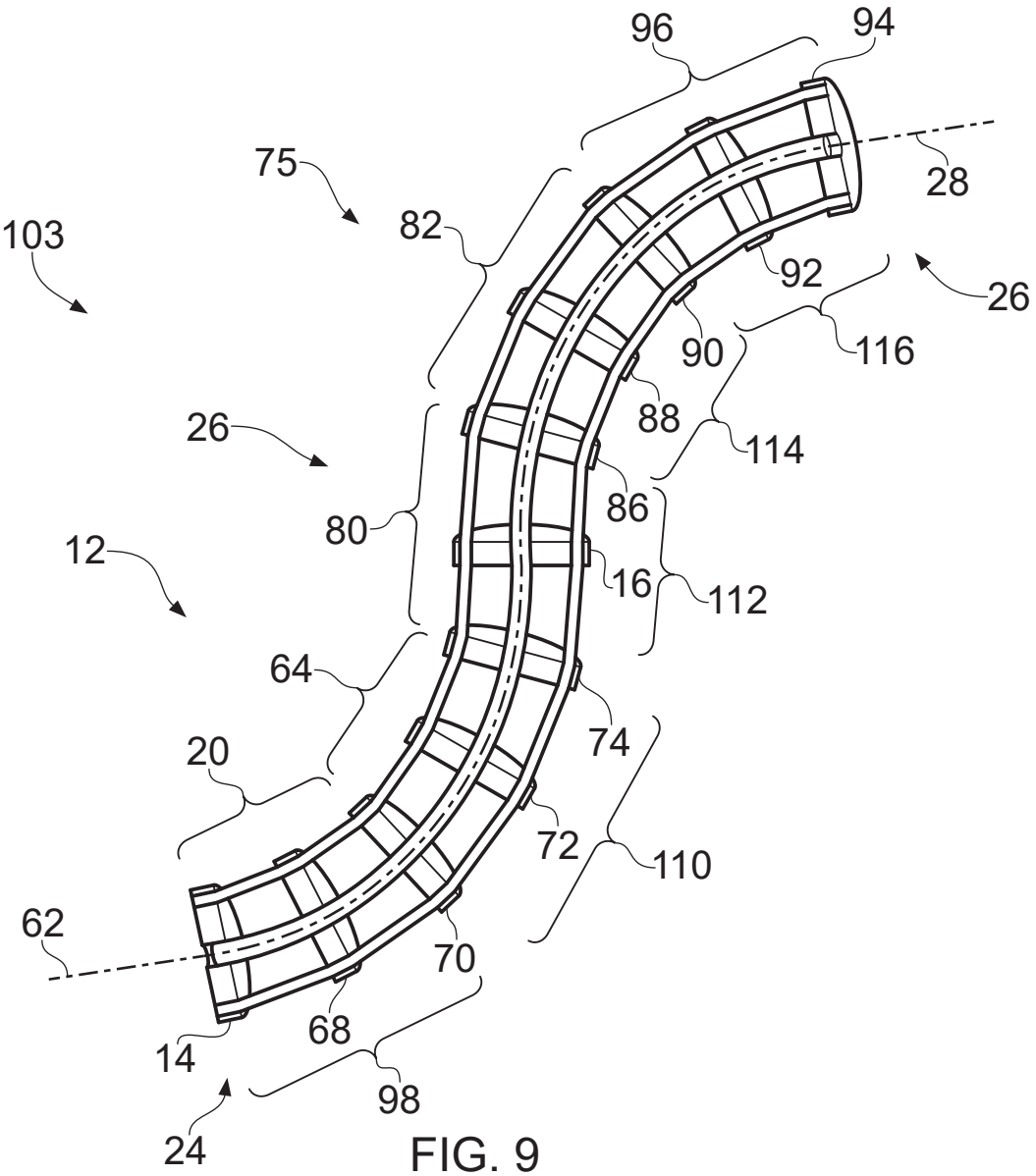

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FIG. 9

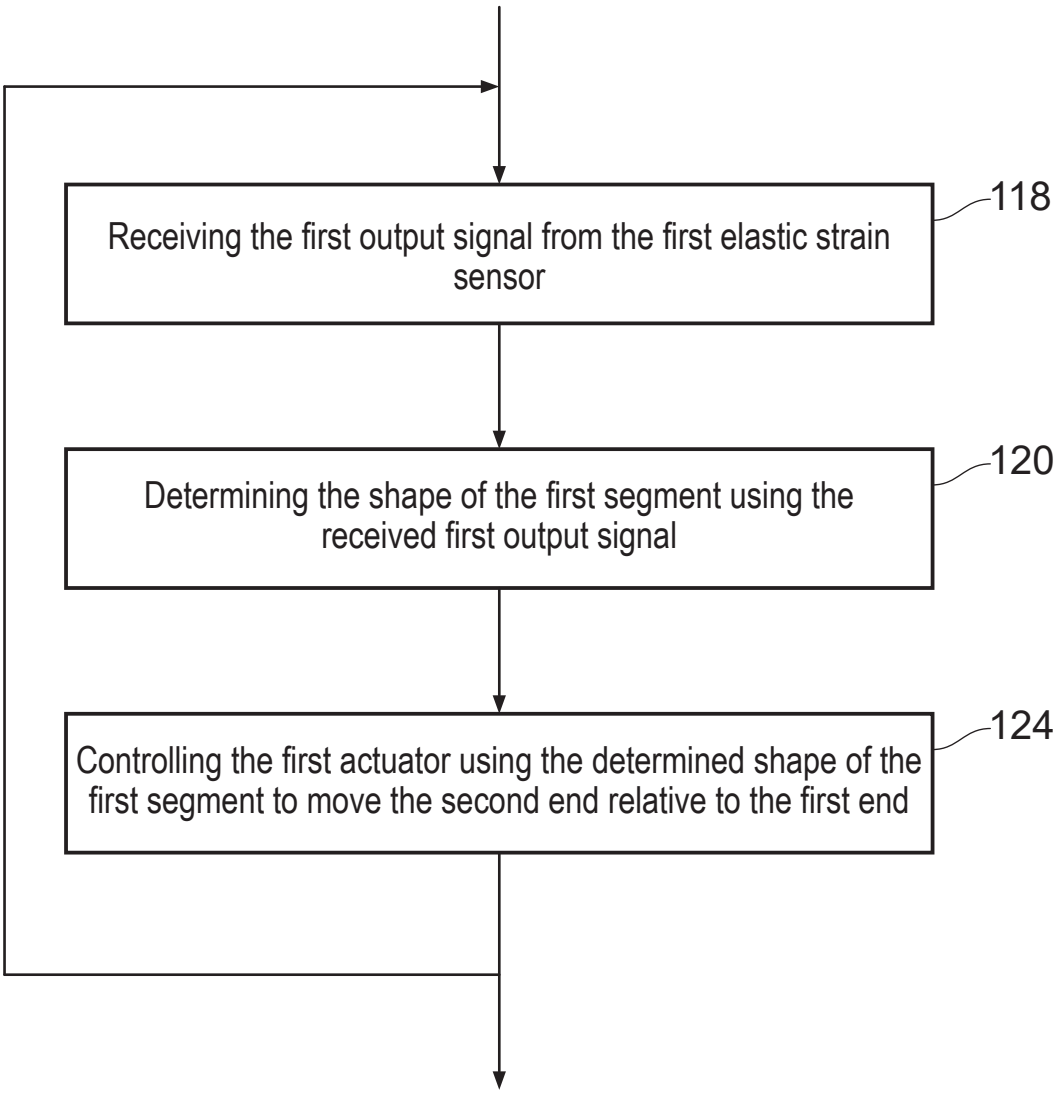

Receiving the first output signal from the first elastic strain sensor
118
Determining the shape of the first segment using the received first output signal
120
Controlling the first actuator using the determined shape of the first segment to move the second end relative to the first end
124

FIG. 10