

a plurality of tendon elements configured to transmit forces from the external actuation elements to the robot arm and the end effector; and

an adapter configured to couple the plurality of tendon elements with the external actuation elements.

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5. The robotic endoscopy apparatus of claim 4, wherein each of the flexible elongate assemblies further comprises:

a flexible sheath configured to cover the plurality of tendon elements; and

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a flexible elongate outer sleeve configured to carry the plurality of tendon elements covered by the flexible sheath.

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6. The robotic endoscopy apparatus of claim 4, wherein each of the flexible elongate assemblies further comprises a collar element configured to surround at least a portion of the flexible elongate outer sleeve at a predetermined distance away from a distal end of the end effector and configured to engage longitudinal translation mechanism to enable longitudinal translation of at least one of the flexible elongate assemblies across a predetermined distance range.

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7. The robotic endoscopy apparatus of claim 1, wherein at least one of the flexible elongate assemblies is a flexible imaging endoscope assembly comprising:

an imaging unit configured to capture images of an environment external to the distal end of the flexible elongate shaft in which the end effectors reside;

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a plurality of tendon elements configured for coupling the external actuation elements to the imaging unit; and

an adapter by which the plurality of tendon elements can be interfaced with particular external actuation elements.